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# RI600/4 V.1.00

User's Manual  
Real-time OS for RX600 Series

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## Preface

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This manual describes how to use the RI600/4, for the RX600 series micro-computer before using the RI600/4, please read this manual.

### □ Notes on Descriptions

- Prefix
  - Prefix "0x" indicates hexadecimal numbers. Numbers with no prefix are decimal.
- "\ " is the directory delimiter.
- "cfg file" indicates kernel configuration file.
- XXX.YYY
  - (1) Definition item of cfg file
  - (2) Structure member
  - (3) Bit(s) of register
- [XXX->YYY]
  - "->" indicates menu option. (e.g.: [File -> Save])
- \$(xxxx)
  - Custom placeholder using in the High-performance Embedded Workshop

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# 1. Composition of This Manual

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This manual is composed of the following chapters.

## □ 2. Overview

Presents an outline of this product.

## □ 3. Introduction to the Kernel

Describes the concept of this product to be understood before it is used and the basic matters regarding the kernel that is the nucleus of this product.

## □ 4. Kernel Functions

Describes various functions of the kernel.

## □ 5. Service Call Reference

Shows service call specifications of the kernel.

## □ 6. How to Write Application

Explains how to write tasks and handlers.

## □ 7. Procedure for Generating the Load Module

Outlines the procedure for generating load modules.

## □ 8. Configurator (cfg600)

Explains how to create the cfg file that is input to the command line configurator cfg600 and how to use the cfg600.

## □ 9. Table Generation Utility (mkritbl)

Explains how to use the table generation utility mkritbl.

## □ 10. GUI Configurator

Presents general information about the GUI configurator. See online help for details on how to use the GUI configurator.

**□ 11. Sample Program**

Explains about the sample application.

**□ 12. Method for Calculating the Stack Size**

Explains how to calculate the stack sizes needed for tasks or handlers.

## 2. Overview

---

### 2.1 Features

#### (1) Compliant with $\mu$ ITRON 4.0 Specification

The RI600/4 was developed based on  $\mu$ ITRON 4.0 specification, the latest version of  $\mu$ ITRON specifications. Therefore, the knowledge acquired from  $\mu$ ITRON specification-related various publications or seminars, etc. can be made use of directly. In addition, the application programs developed using other  $\mu$ ITRON-compliant real-time OS's can be ported to the RI600/4 relatively easily.

#### (2) Increased processing speed

By taking advantage of the RX600-series microcomputer architecture, the processing speed is significantly increased.

#### (3) Systems always built to minimum size by automatically selecting only the necessary modules

The RI600/4 kernel is supplied in RX600-series object library form. This means that from among numerous functional modules of the kernel, only those that an application uses are automatically selected, thanks to the functionality the linkage editor has. Therefore, systems are always generated in minimum size.

#### (4) Efficient development possible by making use of the integrated development environment

Renesas' integrated development environment, or High-performance Embedded Workshop, can be used as you proceed with development work. High-performance Embedded Workshop supports the function to generate workspaces for RI600/4-compatible applications. Furthermore, the real-time OS debug functions of High-performance Embedded Workshop are also usable for the RI600/4.

#### (5) Kernel building made easy by the configurator

The RI600/4 comes with the command line configurator `cfg600`. By only writing various kernel-building information in a text-format `cfg` file, it is possible to build the kernel. This configurator information, as it is created in text form, can be altered and maintained easily.

In addition, a GUI version of the configurator is available. The GUI configurator permits you to build the kernel easily without the need to learn about the description format of the `cfg` file.

## 2.2 Supplied Software Composition

### (1) Kernel

This is the real-time OS body for RX600-series microcomputers.

### (2) cfg600 (command line configurator)

This is a tool to build the kernel. It accepts as its input the cfg file created by the user and outputs a kernel definition file.

### (3) mkritbl (table generation utility)

This is the command line tool that by gathering the service call information used by an application, generates the service call and interrupt vector tables most suitable for the application.

### (4) GUI configurator

This is a tool to build the kernel. From the kernel-building information supplied on the GUI screen, it outputs a cfg file.

## 2.3 Operating Environment

The operating environment is shown in Table 2.1.

Table 2.1 Operating Environment

Item	Operating Environment
Target CPU core	RX CPU
Host machine	IBM-PC/AT compatible machine operated under Windows® 2000, Windows® XP, or Windows Vista®
Compiler	Renesas C/C++ Compiler Package for RX Family



---

## 3. Introduction to the Kernel

---

### 3.1 Operating Principle of the Kernel

The kernel program is the nucleus of the realtime operating system. The kernel enables one CPU to appear as if multiple CPUs are operating. How does the kernel do this? As is shown in Figure 3.1, the kernel switches operation between various tasks as required.

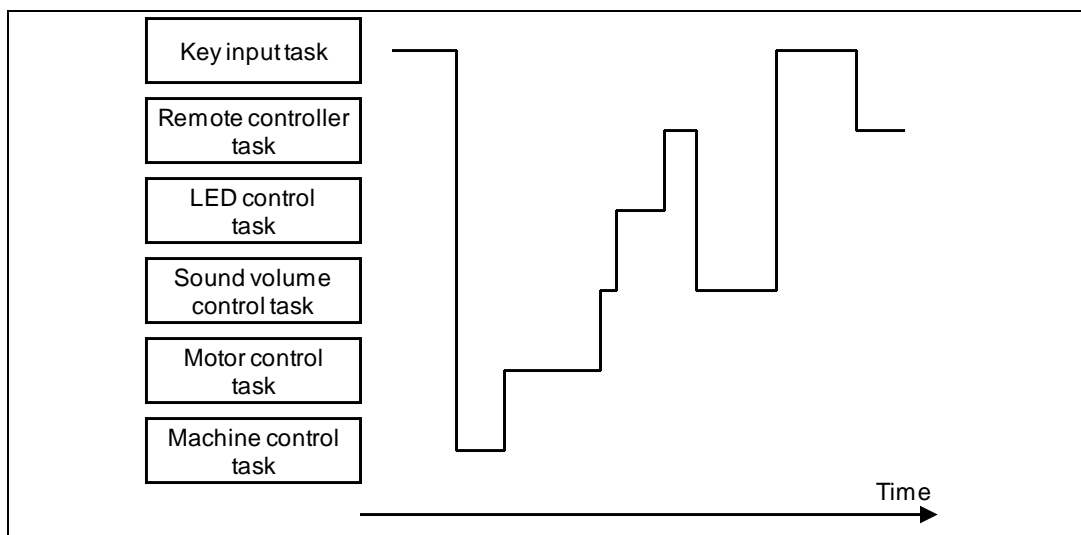


Figure 3.1 Operation of Multiple Tasks

This switching between tasks is called task dispatch. The kernel dispatches tasks in the following cases.

- When a task itself requests a dispatch
- When an event (such as an interrupt) outside the current task requests a dispatch

This means that tasks are not switched at predetermined intervals as in a time-sharing system. This type of scheduling is generally called event-driven.

After a task is dispatched, execution of the task resumes from the point at which it was previously suspended (Figure 3.2).

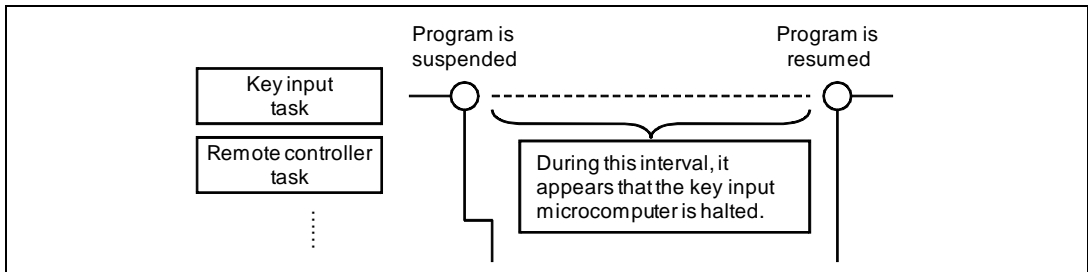


Figure 3.2 Suspending and Resuming a Task

In Figure 3.2, it appears to the programmer that the key input task or its microcomputer is halted while another task assumes execution control.

By restoring the contents of CPU registers that were stored when a task was suspended, the kernel resumes the execution of a task from the state in which it was suspended. In other words, dispatching a task means saving the contents of the CPU registers for the task currently being executed in a memory area prepared for the management of that task, and restoring the contents of the CPU registers for the task for which execution is being resumed (Figure 3.3)

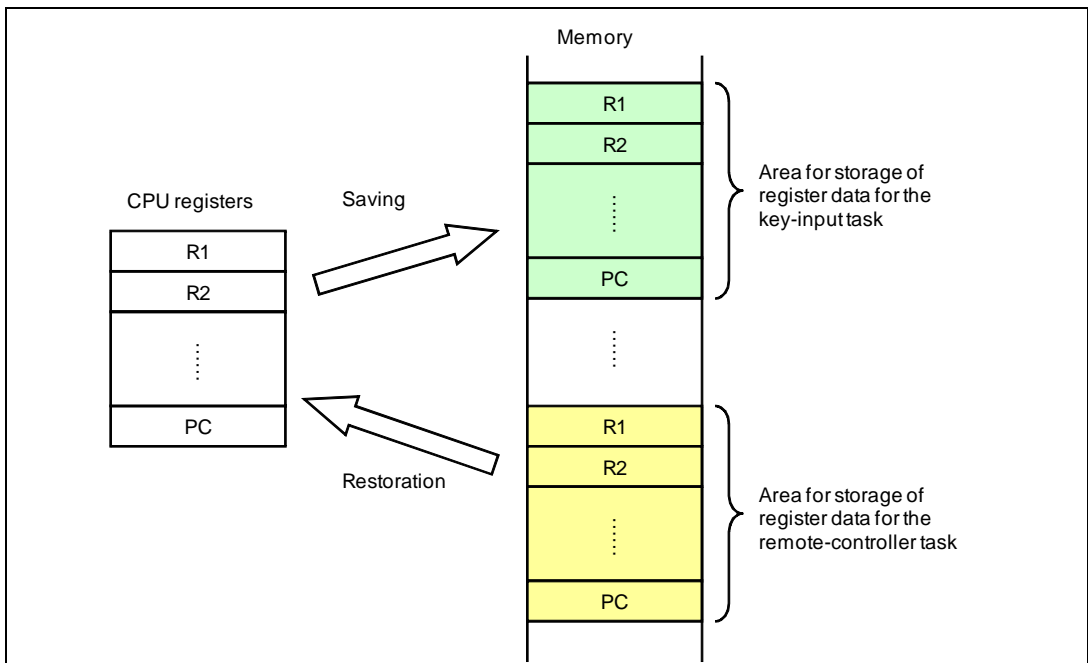


Figure 3.3 Task Dispatch

As well as the CPU registers, task execution requires stack areas. Separate stack area must be allocated for each task.

## 3.2 Service Call

How does the programmer use the kernel functions in a program?

First, it is necessary to call up kernel function from the program in some way or other. Calling a kernel function is referred to as a service call. Task activation and other processing operations can be initiated by such a service call (Figure 3.4).

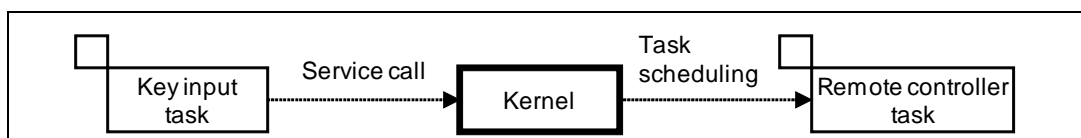


Figure 3.4 Service Call

This service call is realized by a function call when the application program is written in C language, as shown below

```
act_tsk(ID_TASK1);
```

## 3.3 Object

The processing objectives of service calls, such as tasks or semaphores, are called objects. Objects are distinguished by their ID numbers.

However, if a task number is directly written in a program, the resultant program would be very low in readability. If, for instance, the following is entered in a program, the programmer is constantly required to know what the No. 1 task is.

```
act_tsk(1);
```

Further, if this program is viewed by another person, he/she does not understand at a glance what the No. 1 task is.

To avoid such inconvenience, the RI600/4 provides means of specifying the task by name (ID name). The program named "configurator cfg600," which is supplied with the RI600/4, then automatically converts the task name to the task ID number. To be more specific, the cfg600 outputs the header file "kernel\_id.h" which includes definitions of the following type, associating task ID names with task ID numbers.

```
#define ID_TASK1 1
```

Figure 3.5 is a schematic view of the task identification system.

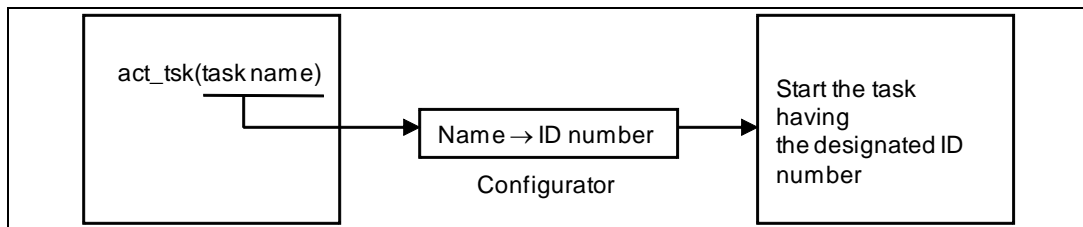


Figure 3.5 Task Identification

With this task identification system, our earlier example is now as follows.

```
act_tsk(ID_TASK1); /* Start the task having the ID name "ID_TASK" */
```

This call specifies invocation of the task corresponding to "ID\_TASK1". Also note that the compiler's pre-processor converts task names to ID numbers in the generation of an executable program. Therefore, this feature does not reduce processing speeds.

Although the example on this section just referred to task identification, other objects that have ID numbers can also be given ID names.

## 3.4 Task

### 3.4.1 Task State

The kernel checks the task state to control whether to execute a task. For example, Figure 3.6 shows the state of the key input task and its execution control. When a key input is detected, the kernel must execute the key input task; that is, the key input task enters the RUNNING state. While waiting for a key input, the kernel does not need to execute the key input task; that is, the key input task is in the WAITING state.

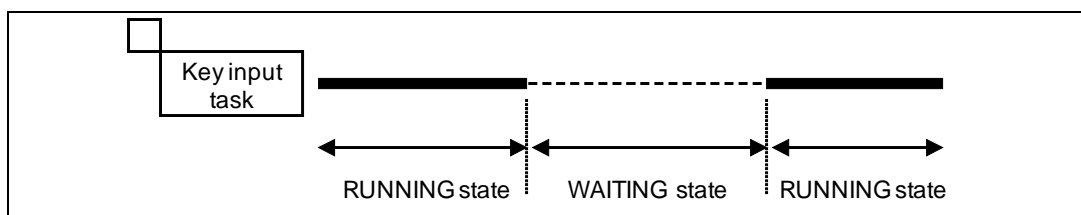


Figure 3.6 Task States

The kernel controls transitions between six states, including the RUNNING and WAITING states, as shown in Figure 3.7. A task makes the transitions between these six states.

#### (1) DORMANT state

The task has been registered in the kernel, but has not yet been initiated, or has already been terminated.

#### (2) READY state

The task is ready for execution, but cannot be executed because another higher priority task is currently running.

#### (3) RUNNING state

The task is currently running. The kernel puts the READY task with the highest priority in the RUNNING state.

#### (4) WAITING state

When the task issues a service call such as `tslp_tsk` and the specified conditions are not satisfied, the task enters the WAITING state. A task is released from the WAITING state by the service call (such as `wup_tsk`) that corresponds to the call which initiated the WAITING state, after which the task enters the READY state.

#### (5) SUSPENDED state

A task has been suspended by another task through `sus_tsk`.

#### (6) WAITING-SUSPENDED state

This state is a combination of the WAITING state and SUSPENDED state.



### 3.4.2 Task Scheduling (Priority and Ready Queue)

For each task, a task priority is assigned to determine the priority of processing. A smaller value indicates a higher priority level and level 1 is the highest priority. The range of available priorities is 1 to `system.priority` as defined in the `cfg` file.

The kernel selects the highest-priority task from among the `READY` tasks and puts it in the `RUNNING` state.

The same priority can be assigned to multiple tasks. When there are multiple `READY` tasks with the highest priority, the kernel selects the first task to have become `READY` and puts it in the `RUNNING` state. To implement this behavior, the kernel has ready queues, which are queues of `READY` task waiting for execution.

Figure 3.8 shows the ready queue configuration. A ready queue is provided for each priority level, and the kernel selects the task at the head of the non-empty ready queue for the highest priority and puts it in the `RUNNING` state.

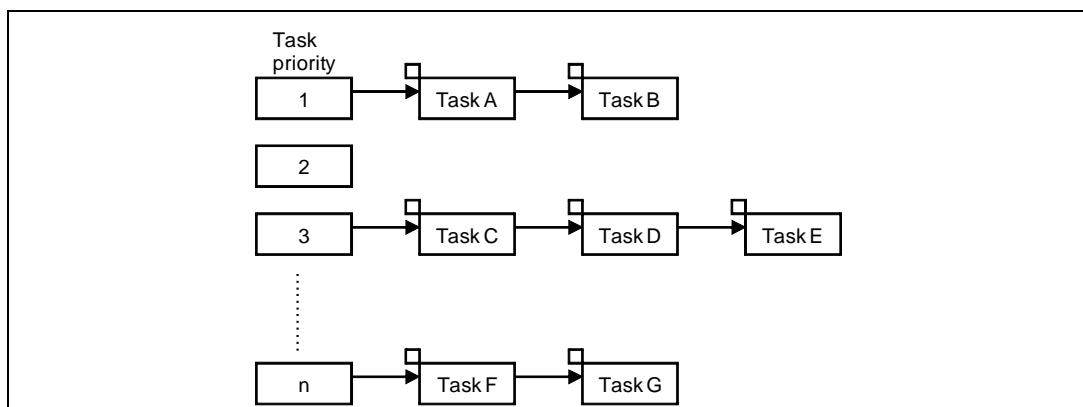


Figure 3.8 Ready Queues (Waiting for Execution)

### 3.4.3 Task Waiting Queue

A service call can make a task wait (enter the WAITING state) until a condition designated in terms of objects (such as semaphores and eventflags) has been satisfied. For some types of objects, two or more tasks may be in the WAITING state. Attributes that select the order in which waiting tasks are handled are specifiable when the objects are created. The specifiable attributes are TA\_TFIFO (handling on an FIFO basis) or TA\_TPRI (handling on a priority basis).

Tasks leave the WAITING state in the order specified for the waiting queue. Figure 3.9 and Figure 3.10 show the order of task handling for objects with the respective attributes, where task D (priority: 9), task C (priority: 6), task A (priority: 1), and task B (priority: 5) have joined the waiting queue, in that order.

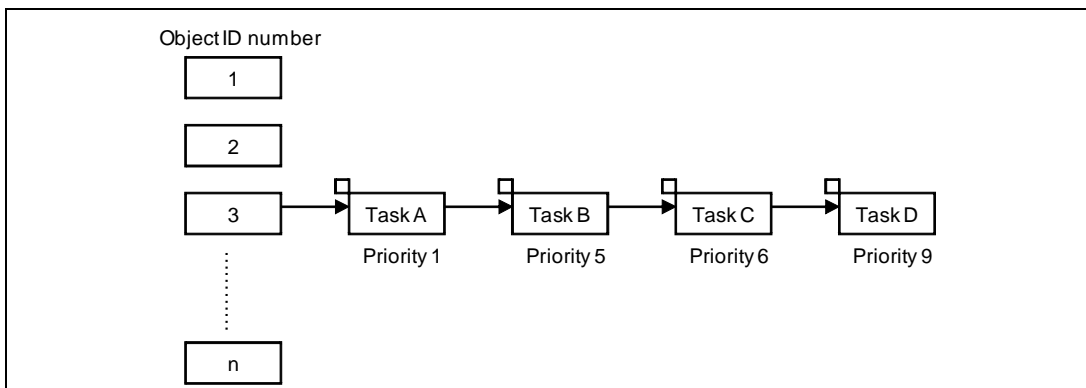


Figure 3.9 Waiting Queue with the Attribute TA\_TPRI

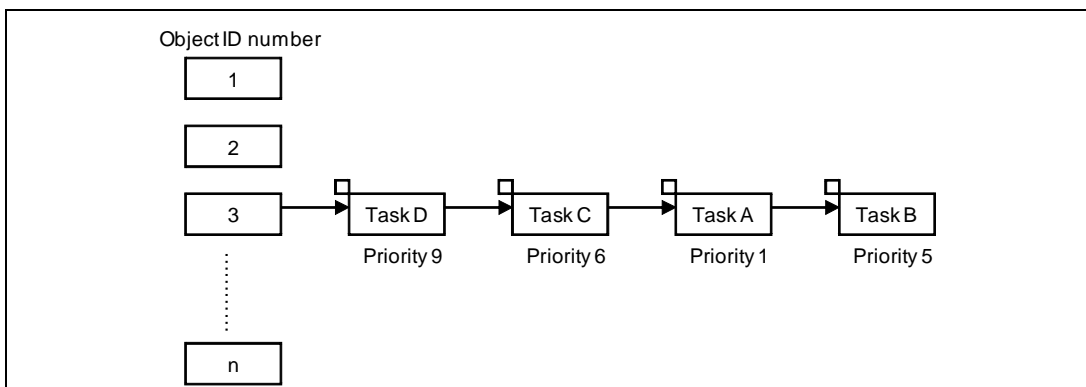


Figure 3.10 Waiting Queue with the Attribute TA\_TFIFO



## 3.5 System State

The system state is classified into the following orthogonal states.

- Task context / non-task context
- Dispatching-disabled state / Dispatching-enabled state
- CPU-locked state / CPU-unlocked state

The system operations and available service calls are determined based on the above system states.

### 3.5.1 Task Context and Non-Task Context

System is in either task contexts or non-task contexts. The difference between task contexts and non-task contexts is described in Table 3.1.

Table 3.1 Task Context and Non-Task Context

Item	Task Context	Non-Task Context
Available service calls	Service calls that can be called from task context	Service calls that can be called from non-task context
Task scheduling	Refer to sections 3.5.2 and 3.5.3	Does not occur

The following forms of processing are executed in non-task contexts.

- Interrupt handlers
- Time event handlers (cyclic handlers and alarm handlers)

### 3.5.2 Dispatching-Disabled State / Dispatching-Enabled State

System is in either the dispatching-disabled state or the dispatching-enabled state. In the dispatching-disabled state, task scheduling is not allowed and service calls that place the current task in the WAITING state cannot be used.

The following service calls changes the system state to the dispatching-disabled state.

- `dis_dsp`
- `chg_ims`, that changes the interrupt mask to other than 0

The following service calls changes the system state to the dispatching-enabled state.

- `ena_dsp`
- `chg_ims`, that changes the interrupt mask to 0

Issuing the `sns_dsp` service call will check whether the system is in the dispatching-disabled state or not.

It is possible to control it exclusively with tasks by using the dispatching-disabled state. However, because other tasks cannot execute while the dispatching-disabled, it influences the behavior of the entire system. To control between tasks exclusively, semaphore or mutex is recommended to be used as much as possible. It is necessary to shorten the time of the dispatching-disabled state as much as possible.

### 3.5.3 CPU-Locked State / CPU-Unlocked State

System is in either the CPU-locked state or the CPU-unlocked state. In the CPU-locked state, interrupts and task scheduling are not allowed. Note, however, that non-kernel interrupts are allowed.

Any service calls that make tasks enter the WAITING state cannot be issued. Issuing the `loc_cpu` or `iloc_cpu` service call changes the system state to the CPU-locked state. Issuing an `unl_cpu` or `iunl_cpu` will return the system state to the CPU-unlocked state. In addition, issuing the `sns_loc` service call will check whether the system is in the CPU-locked state or not.

Service calls that can be issued in the CPU-locked state are restricted to those listed in Table 3.2.

Table 3.2 Service Calls that can be issued in the CPU-Locked State

<code>loc_cpu, iloc_cpu</code>	<code>unl_cpu, iunl_cpu</code>	<code>sns_ctx</code>	<code>sns_loc</code>	<code>sns_dsp</code>
<code>sns_dpn</code>	<code>vsta_knl, ivsta_knl</code>	<code>vsys_dwn, ivsys_dwn</code>	<code>ext_tsk *</code>	

Note: This service call cancels the CPU-locked state.

It is possible to control it exclusively with kernel interrupt processings or tasks and kernel interrupt processings by using the CPU-locked state. However, because other tasks cannot execute and kernel interrupts are masked while the CPU-locked, it influences the behavior of the entire system. It is necessary to shorten the time of the CPU-locked state as much as possible.

### 3.5.4 Dispatching-Pending State

The state that task-dispatching is pended is called the dispatching-pending state. To be more specific, each of the following cases corresponds to the dispatch-pending state.

- Non-task context
- Dispatching-disabled state
- CPU-locked state

The `sns_dpn` service call can be used to check if the system is in the dispatch-pending state.

## 3.6 Processing Units and Precedence

An application program is executed in the following processing units.

- (1) Task  
A task is a unit controlled by multitasking.
- (2) Interrupt handler  
An interrupt handler is executed when an interrupt occurs.
- (3) Time Event Handler (Cyclic Handler and Alarm Handler):  
A time event handler is executed when a specified cycle or time has been reached.

The various processing units are processed in the following order of precedence.

- (1) Interrupt handlers, time event handlers
- (2) Dispatcher (part of kernel processing)
- (3) Task

The dispatcher is kernel processing that switches the task being executed. Since interrupt handlers and time event handlers have higher precedence than the dispatcher, no tasks are executed while these handlers are executing.

The precedence of an interrupt handler becomes higher when the interrupt level is higher.

The precedence of a time event handler is the same as the timer interrupt level (clock.IPL).

The order of precedence for tasks depends on the priority of the tasks.

## 3.7 Interrupts

When an interrupt occurs, the interrupt handler defined in the cfg file is initiated.

### 3.7.1 Type of Interrupt

Interrupt is classified into kernel interrupt and non-kernel interrupt.

- **Kernel Interrupt**

An interrupt whose interrupt priority level is lower than or equal to the kernel interrupt mask level (`system.system_IPL`) is called the kernel interrupt.

Service calls can be issued from within a kernel interrupt handler.

Note, however, that handling of kernel interrupts generated during kernel processing may be delayed until the interrupts become acceptable.

- **Non-Kernel Interrupt**

An interrupt whose interrupt priority level is higher than the kernel interrupt mask level (`system.system_IPL`) is called the non-kernel interrupt. And, fixed vector interrupts are also classified into non-kernel interrupt.

No service calls can be issued from within a non-kernel interrupt handler.

Non-kernel interrupts generated during service-call processing are immediately accepted whether or not kernel processing is in progress

Figure 3.11 shows the relationship between the non-kernel interrupt handlers and kernel interrupt handlers where the kernel mask level is set to 10.

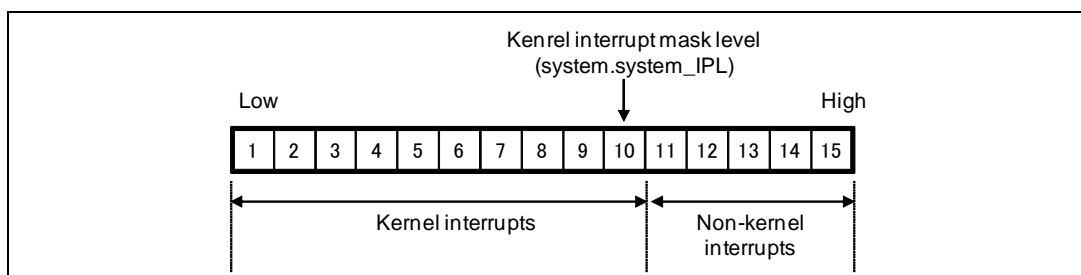


Figure 3.11 Interrupt handler IPLs

### 3.7.2 I bit and IPL bit of the PSW Register

In the CPU specification, all interrupts are masked when I bit is 0, and interrupts at the level below the IPL bit value is masked when I bit is 1.

Please refer to the next paragraph for the change in I bit and the IPL bit by the application.

#### (1) Task

An initial value of the I bit is 1, and an initial value of the IPL bit is 0. In a word, all the interruptions are permitted.

An task must not change the I bit to 0. Note, The RI600/4 does not provide a method to change the I bit. In the change of IPL, there is a method of using `loc_cpu` or `chg_ims`.

#### (2) Interrupt Handler

An initial value of the I bit is 1 when the handler is defined to be enable multiplex interrupts (`pragma_switch=E`). When it is not so, an initial value of the I bit is 0.

An initial value of the IPL bit is the interrupt priority level. In the change of IPL, there is a method of using `iloc_cpu` or `ichg_ims`.

And the I bit and IPL bit can be changed by an interrupt handler.

#### (3) Time Event Handler

An initial value of the I bit is 1

An initial value of the IPL bit is the interrupt priority level of the timer interrupt.(`clock.IPL` in the `.cfg` file.). In the change of IPL, there is a method of using `iloc_cpu` or `ichg_ims`.

And the I bit and IPL bit can be changed by an time event handler.

#### (4) Contorl in a service call

(a) I bit

When a service call is called from the task context, the service call runs while switching the I bit to 0 and 1.

When a service call is called from the non-task context, the I bit is maintained in the service call.

(b) IPL bit

A service call runs while switching the IPL bit to the value before calling and the kernel interrupt mask level (`system.system_IPL`).

(c) State after a service call ends

The PSW register return to the value before calling. However, the IPL bit is changed by `chg_ims`, `ichg_ims`, `loc_cpu`, `iloc_cpu`, `unl_cpu`, or `iunl_cpu`.

### 3.7.3 Disabling Interrupts

To disable interrupts, follow one of the methods described below.

#### (1) Disable unspecified interrupts (Change I bit and IPL bit of the PSW register)

- (a) Putting into the CPU-locked state  
 In the CPU-locked state, PSW.IPL is set to the kernel interrupt mask level (`system.system_IPL`). Therefore, it is only the kernel interrupts that are disabled in the CPU-locked state. To disable non-kernel interrupts, follow the method (b) or (c).  
 Also, when in the CPU-locked state, the usable service calls are subject to some limitations. See Section 3.5.3, "CPU-Locked State / CPU-Unlocked State."
- (b) Use `chg_ims` or `ichg_ims` to alter PSW.IPL.  
 In non-task context, do not lower the IPL bit more than the value when the handler is started.  
 In task-context, the system enters to dispatching-disabled state when the IPL bit is changed to other than 0, and the system enters to dispatching-enabled state when the IPL bit is changed to 0.  
 Usually, do not call `ena_dsp` while having changed the IPL bit to other than 0. If calling `ena_dsp`, the system enters to dispatching-enabled state. The PSW register is changed to the value for dispatched task, so the IPL may be lowered.
- (c) Handlers (non-task context) can change the I bit and IPL bit directly. However, do not lower the IPL bit more than the value when the handler is started.  
 Note, the compiler provides following intrinsic functions for handling PSW register.
  - `set_ipl()` : Changes the IPL bit of the PSW register
  - `get_ipl()` : Refers to the IPL bit of the PSW register
  - `set_psw()` : Changes the PSW register
  - `get_psw()` : Refers to the PSW register

#### (2) Disable specified interrupts

Change Interrupt Request Registers in the interrupt controller (ICU) or control registers of the I/O to disable specified interrupts.

### 3.7.4 Usable Service Calls

- (1) Since the interrupt handler is classified as belonging to non-task contexts, the task context-only service calls cannot be used in the interrupt handler.
- (2) When the PSW.IPL is larger than or equal to the kernel interrupt mask level (`system.system_IPL`), such as non-kernel interrupt handlers, do not call service calls<sup>1</sup>. If calling, the service call returns error `E_CTX`. In this case, the PSW.IPL temporarily falls on the kernel interrupt mask level. Please use this error only for the purpose of debugging.

<sup>1</sup> Except `chg_ims`, `ichg_ims`, `get_ims`, `iget_ims`, `vsta_knl`, `ivsta_knl`, `vsys_dwn`, and `ivsys_dwn`

### 3.7.5 Regarding Non-maskable Interrupt and Exceptions

The non-maskable interrupt are handled as non-kernel interrupt.

Furthermore, the following exceptions that are caused by instruction execution are handled as non-kernel interrupt. Note, the E\_CTX error is not detected when service call is issued from these interrupt handlers.

- Undefined instruction exception
- Privileged instruction exception
- Access exception
- Floating-point exception
- INT instruction exception
- BRK instruction exception

### 3.7.6 Fast Interrupt Function of the RX Microcomputer

The RX microcomputer supports the "fast interrupt" function. Only one interrupt source can be made the fast interrupt. The fast interrupt is handled as the one that has interrupt priority level 15. To use the fast interrupt function, make sure there is only one interrupt source that is assigned interrupt priority level 15.

For the fast interrupt function to be used in this kernel, it is necessary that the interrupt concerned be handled as a non-kernel interrupt. In other words, the kernel interrupt mask level (system.system\_IPL) must be set to 14 or below.

And "os\_int = NO;" and "pragma\_switch = F;" are required for interrupt\_vector[] definition.

And the FINTV register must be initialized to the start address of the handler by application.

## 3.8 Stacks

Stack is classified into user stack and system stack.

- **User Stack**

One user stack is provided for each task. User stack for each task is generated by specifying the size and section name in the cfg file.

- **System Stack**

The system stack is used by non-task context and the kernel. There is one system stack in the system.

The system stack is generated by specifying system.stack\_size in the cfg file.

## 4. Kernel Functions

This section mainly describes the functions and usage of kernel service calls

### 4.1 Module Structure

The kernel consists of the modules shown in Figure 4.1. Each of these modules is composed of functions that exercise individual module features.

The kernel is supplied in the form of a library, and only necessary features are linked at the time of system generation. More specifically, only the functions used are chosen from those which comprise these modules and linked by means of the Linkage Editor. However, the scheduler module, part of the task management module, and part of the time management module are linked at all times because they are essential feature functions.

The applications program is a program created by the user. It consists of tasks, interrupt handler, alarm handler, and cyclic handler.

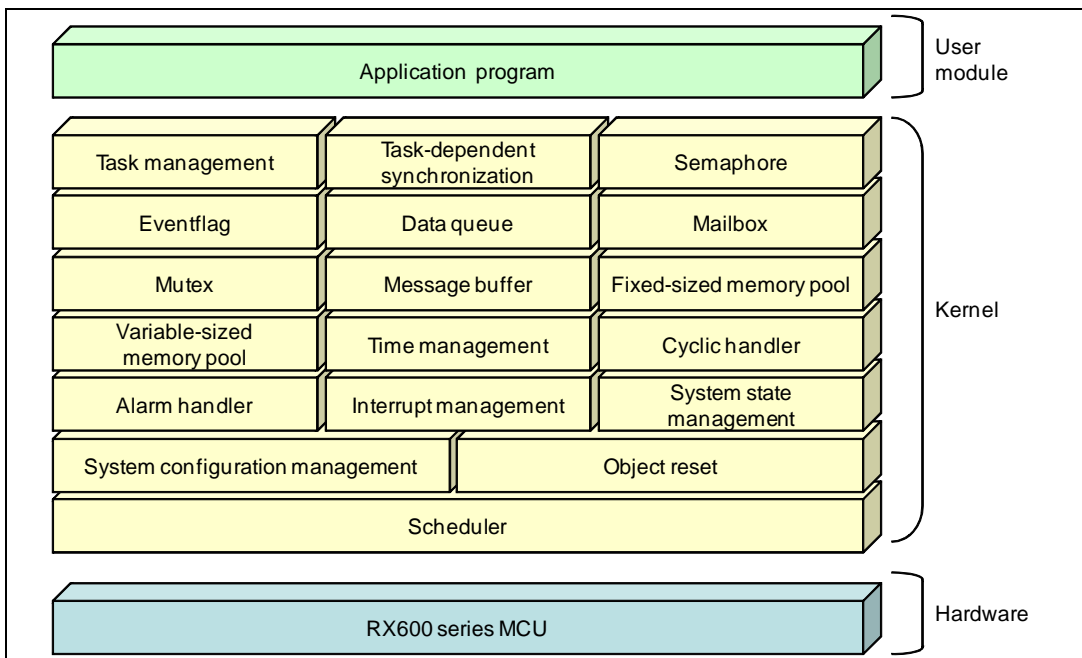


Figure 4.1 Kernel Structure



## 4.2 Module Overview

### (1) Scheduler

Forms a task processing queue based on task priority and controls operation so that the high-priority task at the beginning in that queue (task with small priority value) is executed.

### (2) Task Management Module

Exercises task operation such as activation, termination, or changing task priority

### (3) Task-Dependent Synchronization Module

Accomplishes inter-task synchronization by changing the task status from a different task.

### (4) Synchronization and Communication Module

This is the function for synchronization and communication among the tasks by using the objects independent of task. The following five functional modules are offered.

- Semaphore  
The semaphore is the object to prevent resources between tasks from competing.
- Eventflag  
The eventflag is the object that controls the execution control of tasks according to the condition of AND/OR condition of the bit pattern.
- Data Queue  
The data queue is the object to communicate the 1-word (32 bits) data.
- Mailbox  
The mailbox is the object to communicate messages with arbitrary size. The message is not copied, the message address is transferred.
- Mutex  
The mutex is the object to prevent resources between tasks from competing. The mutex has the function to evade the priority inversion problem.
- Message Buffer  
The message buffer is the object to communicate messages with arbitrary size. The message is copied,

### (5) Fixed-sized Memory Pool

The fixed-sized memory pool is the object to allocate the fixed-sized memory block dynamically.

### (6) Variable-sized Memory Pool

The variable-sized memory pool is the object to allocate the memory block with arbitrary size dynamically.

### (7) Interrupt management Module

Makes a return from the interrupt handler.

**(8) Time Management Module**

Sets up the system timer used by the kernel and starts the user-created alarm handler and cyclic handler.

**(9) System Status Management Module**

Changes or refers to the system state.

**(10) System Configuration Management Module**

Gets kernel configuration information.

**(11) Object Reset Module**

Resets data queue, mailbox, message buffer, fixed-sized memory pool, and variable-sized memory pool.

This is the function outside  $\mu$ ITRON 4.0 specification.

## 4.3 Task management Function

The task management functions are used to perform task operations such as activating, ending tasks, and changing task priorities.

To create tasks, writes "task[]" in the cfg file. In the "task[]" statement, following information are specified.

- ID name
- Task entry address
- Size of user stack
- Section name of user stack
- Task initial priority
- Initial state after creation
- Extended information

The kernel offers the following task management function service calls.

### (1) Activates Task (**act\_tsk**, **iact\_tsk**)

Activates the task with the specified ID. Unlike `sta_tsk` and `ista_tsk`, the activation requests by these service calls are queued, but a start code to be passed to the target task cannot be specified in these service calls. Extended information specified at the time of task creation is passed to the target task.

### (2) Cancels Task Activation Requests (**can\_act**, **ican\_act**)

Cancels the activation requests that have been queued for the task with the specified ID.

### (3) Starts Task (with start code) (**sta\_tsk**, **ista\_tsk**)

Activates the task with the specified ID. In either service call, unlike in `act_tsk` or `iact_tsk`, requests for service call startup of this type are not queued, but a start code to be passed to the target task can be specified.

### (4) Terminates Current task (**ext\_tsk**)

Terminates the current task, placing the task in the DORMANT state. If activation requests for the task have been queued, task startup processing is performed again. In this case, the current task behaves as if it has been reset.

Behavior of the task in response to this service call is the same as the task returning from its entry function.

### (5) Terminates Another Task (**ter\_tsk**)

Terminates another task that is not in the DORMANT state and places the task in the DORMANT state. If activation requests for the task have been queued, task startup processing is performed again.

### (6) Changes Task Priority (**chg\_pri**, **ichg\_pri**)

Changes the priority of the task with the specified ID. If the priority of a task is changed while the task is in the

READY or RUNNING state, the ready queue is also updated (Figure 4.2). Moreover, if the target task is placed in the wait queue of an object with the TA\_TPRI attribute, the wait queue is also updated (Figure 4.3).

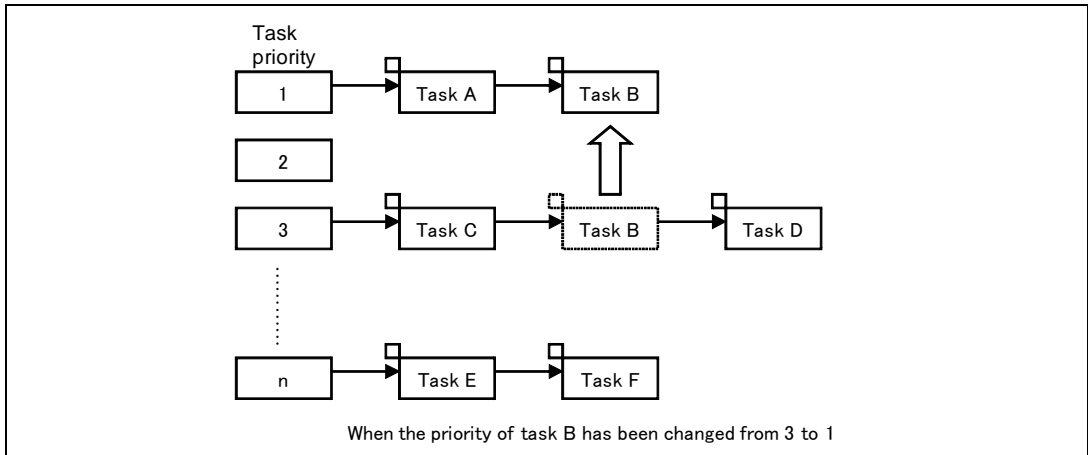


Figure 4.2 Ready Queue When Changing a Task Priority in the READY or RUNNING State

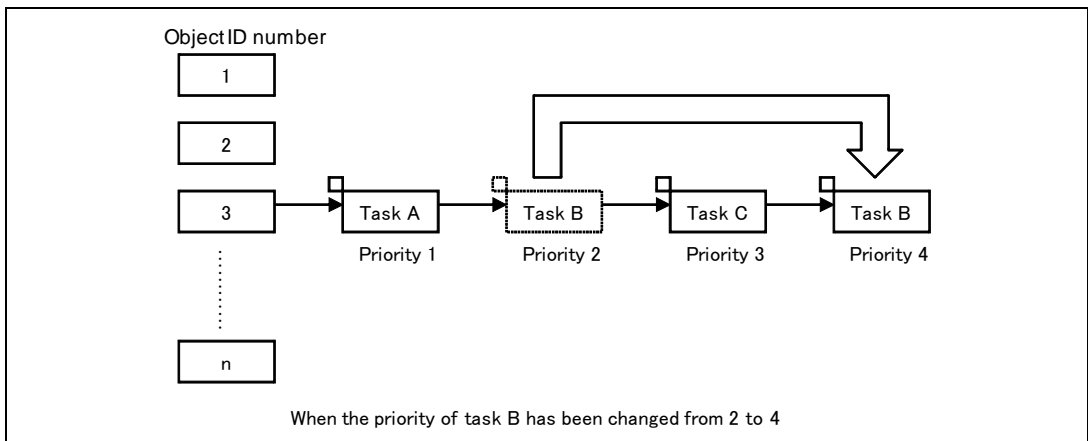


Figure 4.3 Re-Arranging the Wait Queue When Changing Priority of a task waiting for the object with TA\_TPRI Attribute

However, it is generally recommended that these service calls not be used because changing the priority affects the behavior of the entire system.

A task has two priority levels: base priority and current priority. In general operation, these two priority levels are the same; they differ only while the task has a mutex locked. For details, refer to section 4.9, "Mutex."

**(7) Refers to Task Priority (get\_pri, iget\_pri)**

Gets the priority of the task with the specified ID.

**(8) Refers to Task Status (ref\_tsk, iref\_tsk)**

Refers to status of the task with the specified ID.

**(9) Refers to Task Status (Simplified Version) (ref\_tst, iref\_tst)**

Refers to status of the task with the specified ID. Either service call produces less overhead than ref\_tsk or iref\_tsk because it refers to less information.

## 4.4 Task-Dependent Synchronization Function

The task-dependent synchronization functions are used to achieve synchronization between tasks by placing tasks in the WAITING, SUSPENDED, or WAITING-SUSPENDED states, or to wake up tasks in the WAITING state.

The kernel offers the following task-dependent synchronization service calls.

### (1) Sleep Task (slp\_tsk, tslp\_tsk) and Wakes up Task (wup\_tsk, iwup\_tsk)

The slp\_tsk puts the current task to sleep. The task in sleep becomes to the WAITING state.

The tslp\_tsk performs the same function as slp\_tsk except that a timeout period before wakeup is specifiable. The wup\_tsk or iwup\_tsk wakes up a task from sleep state. The waked-up task is released from the WAITING state. While the target task is not in sleep state, the issued wakeup requests are queued. If the task for which wakeup requests have been queued calls slp\_tsk or tslp\_tsk, the wakeup request count is decremented by one (-1) and the task does not enter the WAITING state (Figure 4.4).

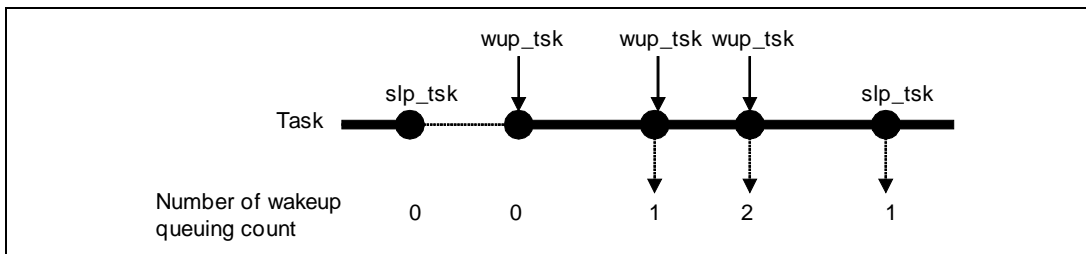


Figure 4.4 Queuing Wakeup Request

### (2) Cancels Task Wakeup Request (can\_wup, ican\_wup)

Cancels the wakeup requests queued for a task with the specified ID (Figure 4.5).

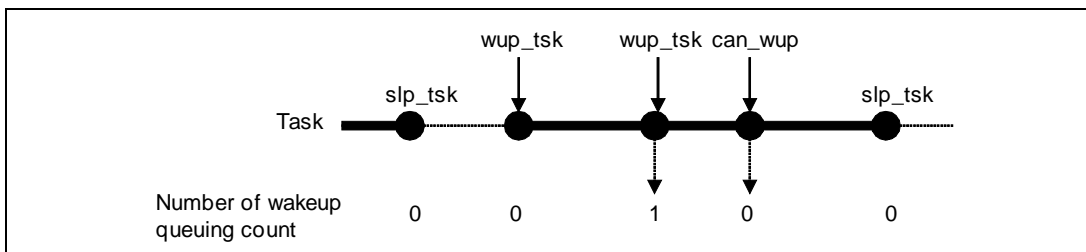


Figure 4.5 Canceling Wakeup Requests

**(3) Suspends Task (sus\_tsk, isus\_tsk) and Resumes Task(rsm\_tsk, irsm\_tsk, frsm\_tsk, ifrsm\_tsk)**

Issuing sus\_tsk or isus\_tsk forcibly suspends the task with the specified ID. If the target task is in the READY state, the task is placed in the SUSPENDED state. If the target task is in the WAITING state, the task is placed in the WAITING-SUSPENDED state.

Only one suspension request can be nested, if sus\_tsk or isus\_tsk is issued to a task in the SUSPENDED state, the error E\_QOVR is returned.

The rsm\_tsk or irsm\_tsk decrements the suspension counts for a task with the specified ID. When the number reaches 0, the task is taken out of the SUSPENDED state (Figure 4.6).

The frsm\_tsk or ifrsm\_tsk clears the suspension count for a task with specified ID, and the task is taken out of the SUSPENDED state.

Because the maximum suspension count is 1, the behavior of the frsm\_tsk and ifrsm\_tsk is the same as the rsm\_tsk and irsm\_tsk.

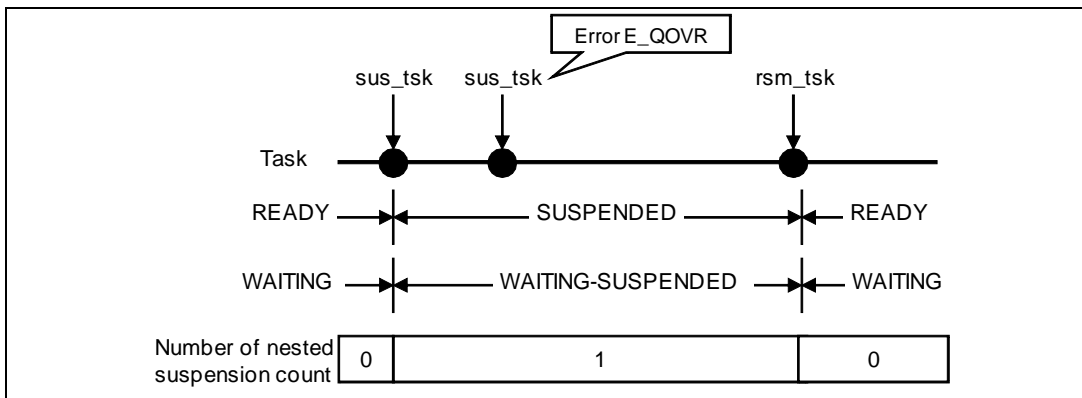


Figure 4.6 Suspending and Resuming Tasks

**(4) Forcible Releases from WAITING State (rel\_wai, irel\_wai)**

The rel\_wai or irel\_wai forcibly releases the task with the specified ID from the WAITING state. Note that neither service call can release a task from the SUSPENDED state.

**(5) Delays Task (dly\_tsk)**

The dly\_tsk delays execution of the current task during the specified time. The current task enters to the WAITING state.

## 4.5 Semaphore

A semaphore is an object used to prevent conflicts over resources such as devices or variables shared by multiple tasks. For example, if task switching occurs while task A is updating a shared variable and task B refers to this variable when updating of its value is not complete, task B may incorrectly read the shared variable. Such conflicts can be prevented by using semaphores.

A semaphore provides exclusive control and a synchronization function by expressing the existence of a resource or the number of resources as a counter.

Applications must be programmed so that semaphores are associated with resources to be exclusively controlled.

Note the following rules on exclusive control using a semaphore.

- (1) A task should acquire the semaphore before using the associated resource
- (2) A task should release the semaphore after its usage of the resource is finished

To create semaphores, writes "semaphore[]" in the cfg file. In the "semaphore []" statement, following information are specified.

- ID name
- How tasks are queued waiting for the semaphore  
TA\_TFIFO (queued in FIFO order) or TA\_TPRI (queued in order of task priority)
- Initial value of semaphore counter
- Maximum value of semaphore counter

Figure 4.7 shows an example of semaphore usage.

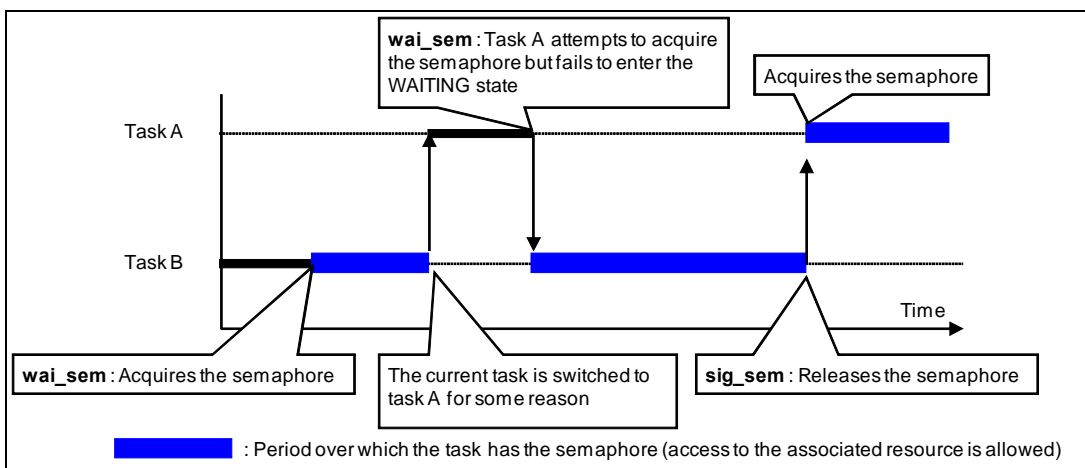


Figure 4.7 Example of Semaphore Usage

Control related to semaphores is implemented by the service calls listed below.



**(1) Acquires Semaphore Resource (wai\_sem, twai\_sem)**

Acquires a semaphore. If the semaphore's counter has a positive value, the counter is decremented by one. If the semaphore cannot be acquired (semaphore count = 0), the task enters the WAITING state.

**(2) Acquires Semaphore Resource (Polling) (pol\_sem, ipol\_sem)**

Acquires a semaphore. The only difference between these service calls and wai\_sem or twai\_sem is that an error is immediately returned and the task does not enter the WAITING state when the semaphore count is 0.

**(3) Releases Semaphore Resource (sig\_sem, isig\_sem)**

Releases a semaphore. When a task is waiting to acquire a semaphore, either service call makes the task leave the WAITING state. If not, the counter is incremented by one.

**(4) Refers to Semaphore Status (ref\_sem, iref\_sem)**

Refers to the state of a semaphore, including its counter and the IDs of waiting tasks.

### 4.5.1 Priority Inversion Problem

When a semaphore is used for exclusive control of a resource, a problem called priority inversion may arise. This refers to the situation where a task that is not using a resource delays the execution of a task requesting the resource.

Figure 4.8 illustrates this problem. In this figure, tasks A and C are using the same resource, which task B does not use. Task A attempts to acquire a semaphore so that it can use the resource but enters the WAITING state because task C is already using the resource. Task B has a priority higher than task C and lower than task A. Thus, if task B is executed before task C has released the semaphore, release of the semaphore is delayed by the execution of task B. This also delays acquisition of the semaphore by task A. From the viewpoint of task A, a lower-priority task that is not even competing for the resource gets priority over task A.

To avoid this problem, use a mutex instead of a semaphore.

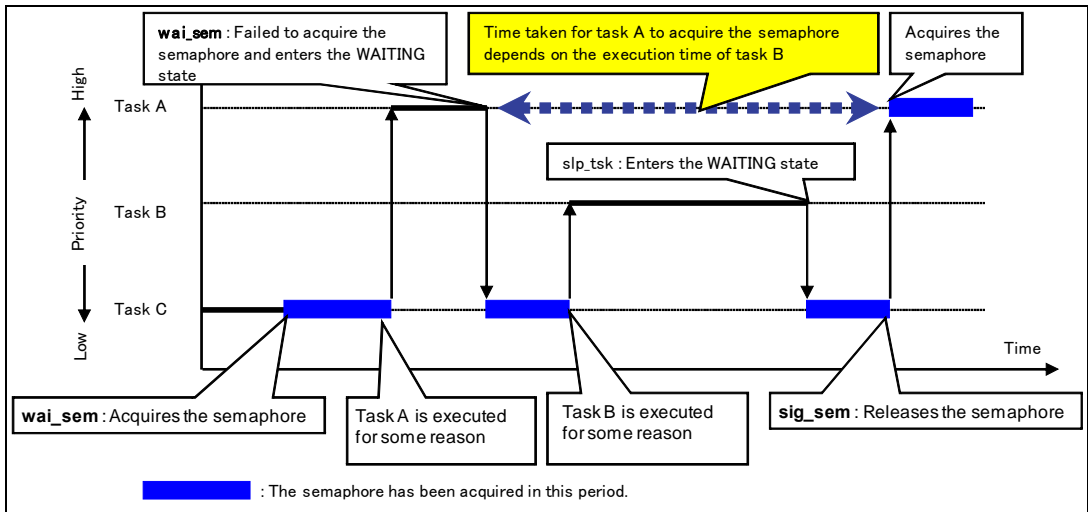


Figure 4.8 Priority Inversion Problem

## 4.6 Eventflag

An eventflag is a group of bits that correspond to events. One event corresponds to one bit. A task can be made to wait for one (OR condition) or all (AND condition) of the specified bits to be set. Whether more than one task is allowed to wait for a specific bit of an eventflag to be set can be selected as an attribute when the eventflag is created. Either of the following attributes is selectable.

- TA\_WMUL : Multiple tasks are permitted to wait
- TA\_WSGL : Multiple tasks not permitted to wait

A TA\_CLR attribute is also specifiable; in this case, the bit pattern of the eventflag is cleared to 0 whenever the wait condition of a task is satisfied.

One feature of the eventflag mechanism is that multiple tasks can be released from the WAITING state at the same time. To allow this, specify the TA\_WMUL attribute. Do not specify the TA\_CLR attribute in this case.

Figure 4.9 shows an example of task execution control by an eventflag. In this figure, six tasks, task A to task F, have been placed in a wait queue. After the flag pattern has been set to 0x0F by the service call `set_flg`, the pattern satisfies the wait conditions for three of the tasks (task A, task C, and task E). These tasks are sequentially removed from the head of the queue.

If this eventflag has the TA\_CLR attribute, when task A is released from the WAITING state, the bit pattern of the eventflag will be set to 0, and task C and task E will not be removed from the queue.

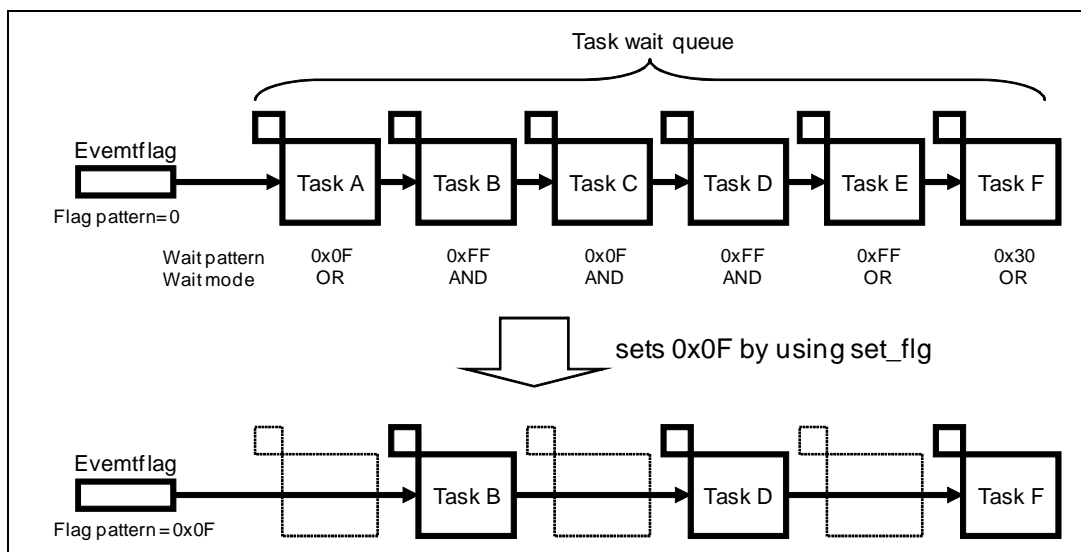


Figure 4.9 Example of Eventflag Usage

To create eventflags, writes "flag[]" in the cfg file. In the "flag []" statement, following information are specified.

- ID name
- How tasks are queued waiting for the semaphore  
TA\_TFIFO (queued in FIFO order) or TA\_TPRI (queued in order of task priority)
- Initial pattern of eventflag
- Multiple wait permission attribute  
TA\_WMUL (multiple tasks are permitted to wait) or TA\_WSGL (multiple tasks not permitted to wait)
- Clear attribute (TA\_CLR)

Control related to eventflags is implemented by the service calls listed below.

### **(1) Waits for Eventflag (wai\_flg, twai\_flg)**

Makes a task wait until specific bits in the eventflag have been set. Select either of the following wait conditions.

- AND condition : Waits until all of the specified bits have been set
- OR condition : Waits until any of the specified bit have been set

When a task is released from the WAITING state, the value of the eventflag at satisfaction of the wait condition is returned to the task that issued this service call. If the TA\_CLR attribute has been specified for the eventflag, the eventflag is also cleared to 0. In this case, the value of the eventflag immediately before it was cleared is returned to the task that issued this service call.

### **(2) Acquires Eventflag (Polling) (pol\_flg, ipol\_flg)**

Checks if specified bits in an eventflag have been set. The only difference between these service calls and wai\_flg or twai\_flg is that an error code is immediately returned and the task does not enter the WAITING state when the condition is not satisfied.

### **(3) Sets Eventflag (set\_flg, iset\_flg)**

Sets an eventflag to a specified bit pattern. This may release tasks with wait conditions that match the pattern.

### **(4) Clears Eventflag (clr\_flg, iclr\_flg)**

Clears specified bits of an eventflag.

### **(5) Refers to Eventflag Status (ref\_flg, iref\_flg)**

Refers to the state of an eventflag, including its bit pattern and the IDs of waiting tasks.

## 4.7 Data Queue

A data queue is an object used to achieve the communication of single word (32-bit units) of data.

Figure 4.10 shows the structure of a data queue.

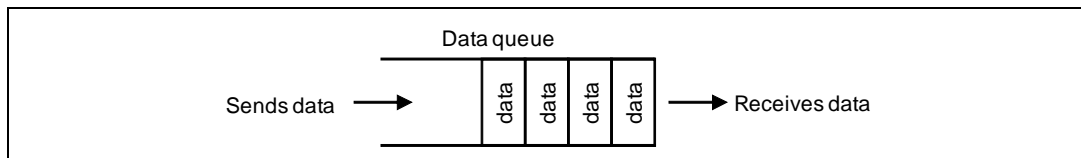


Figure 4.10 Data Queue

Data are sent to a data queue for storage. When data are received from a data queue, the oldest data are taken out first (on an FIFO basis). The maximum number of data items that can be queued in a data queue is specifiable when the data queue is created. A data queue with no storage can be used.

To create data queues, writes "dataqueue[]" in the cfg file. In the "dataqueue[]" statement, following information are specified.

- ID name
- How tasks are queued waiting to send  
TA\_TFIFO (queued in FIFO order) or TA\_TPRI (queued in order of task priority)
- Number of data items that can be stored

Data queues are controlled by the service calls listed below.

### (1) Sends to Data Queue (snd\_dtq, tsnd\_dtq)

Sends a data to an data queue. When the data queue is full of data, the calling task enters the WAITING state.

### (2) Sends to Data Queue (Polling) (psnd\_dtq, ipsnd\_dtq)

Sends a data to a data queue. The only difference between these service calls and snd\_dtq or tsnd\_dtq is that an error code is immediately returned and the calling task does not enter the WAITING state when the data queue is full.

### (3) Forcibly Sends to Data Queue (fsnd\_dtq, ifsnd\_dtq)

Sends a data to a data queue. When the data queue is full of data, the oldest data are deleted and the new data are sent.

**(4) Receives from Data Queue (rcv\_dtq, trcv\_dtq)**

Receives a data from a data queue. When the data queue has no data, the calling task enters the WAITING state. If the data queue was full of data and a task was waiting to send data, this call releases the first task in the wait queue for sending data from the WAITING state.

**(5) Receives from Data Queue (Polling) (prcv\_dtq, iprcv\_dtq)**

Receives a data from a data queue. When the data queue has no data, an error code is returned. If the data queue was full of data and a task was waiting to send data, this call releases the first task in the wait queue for sending data from the WAITING state.

**(6) Refers to Data Queue Status (ref\_dtq, iref\_dtq)**

Refers to the state of a data queue, including the number of data stored in the queue, the ID of task waiting to send, and the ID of task to receive data.

## 4.8 Mailbox

A mailbox is an object used to send or receive messages, which are data with arbitrary size.

Figure 4.11 shows the structure of a mailbox.

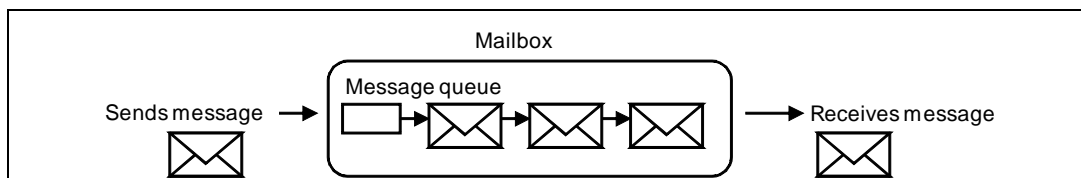


Figure 4.11 Mailbox

High-speed data communications are achieved regardless of the message size because only the addresses where the messages start are sent and received. Applications should create messages in memory areas that are accessible by both the sending and receiving tasks (i.e., messages should not be created in the local variable areas). A sending task should not access the message area after it has sent the message.

Messages transmitted to mailbox are managed by message queue. The messages are received in order of message queue.

Either the following can be selected as the order of message queue.

- TA\_MPRI attribute : Queued in order of message's priority
- TA\_MFIFO attribute : Queued in FIFO order

To create mailboxes, writes "mailbox[]" in the cfg file. In the "mailbox[]" statement, following information are specified.

- ID name
- How tasks are queued waiting to receive  
TA\_TFIFO (queued in FIFO order) or TA\_TPRI (queued in order of task priority)
- How messages are queued  
TA\_MFIFO (queued in FIFO order) or TA\_MPRI (queued in order of message's priority)
- Maximum message priority

Mailboxes are controlled by the service calls listed below.

### (1) Sends to Mailbox (snd\_mbx, isnd\_mbx)

Sends a message to a mailbox.

### (2) Receives from Mailbox (rcv\_mbx, trcv\_mbx)

Receives a message from a mailbox. When the mailbox has no message, the task is in the WAITING state until a message is sent to the mailbox.

**(3) Receives from Mailbox (Polling) (prcv\_mbx, iprcv\_mbx)**

Receives a message from a mailbox. The only difference between these service calls and rcv\_mbx or trcv\_mbx is that an error code is immediately returned and the task does not enter the WAITING state when the mailbox has no message.

**(4) Refers to Mailbox Status (ref\_mbx, iref\_mbx)**

Refers to the address of the first message queued in the mailbox and the IDs of waiting tasks.



## 4.9 Mutex

A mutex is an object used to achieve exclusive control. It differs from a semaphore on the following points.

- (1) A priority ceiling protocol is applied to avoid priority inversion problems.
- (2) A mutex can only be used for exclusive control of a single resource.

Original behavior of the priority ceiling protocol is to make the current priority of the task to the highest ceiling priority of mutexes which are locked by the task. This behavior is achieved by controlling the current priority of the task as follows.

- When a task locks a mutex, changes the current priority of the task to the highest ceiling priority of mutexes which are locked by the task.
- When a task unlocks a mutex, changes the current priority of the task to the highest ceiling priority of mutexes which continues to be locked by the task. When there is no mutex locked by the task after unlock, returns the current priority of the task to the base priority.

However, the RI600/4 kernel adopts simplified priority ceiling protocol because of reducing overhead. Therefore, the underlined part is not processed.

Figure 4.12 shows an example of mutex usage.

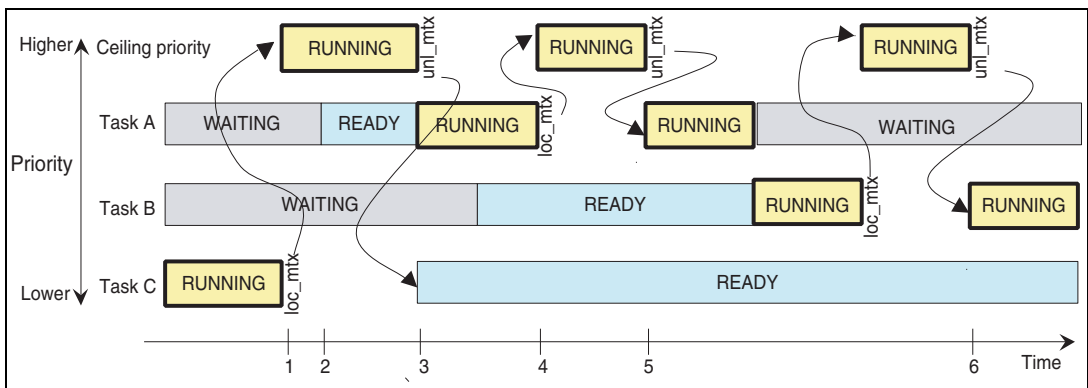


Figure 4.12 Example of Mutex Usage

Description:

- 1 Task C locks a mutex by issuing loc\_mtx. The priority of task C is raised to the ceiling priority specified for the mutex.
- 2 Task A enters the READY state while task C is being executed at the ceiling priority. The priority of task A is higher than that initially specified for task C. However, task C now locks the mutex and

is thus executed at the ceiling priority. Since this is higher than that of task A, task A cannot enter the RUNNING state. In other words, while task C has the mutex locked, execution of task C continues even if task A, with its higher initial priority, becomes ready.

- 3 Task C unlocks the mutex by issuing `unl_mtx`. The priority of task C returns to the initial level and higher-priority task A enters the RUNNING state.
- 4 Task A issues `loc_mtx` to raise its priority to the ceiling priority.
- 5 Task A issues `unl_mtx` to return its priority to the initial level.
- 6 Task B issues `loc_mtx` to raise its priority to the ceiling priority.
- 7 Task B issues `unl_mtx` to return its priority to the initial level.

To create mutexes, writes "mutex[]" in the `cfg` file. In the "mutex[]" statement, following information are specified.

- ID name
- Ceiling priority

Mutexes are controlled by the service calls listed below.

### (1) Locks Mutex (`loc_mtx`, `tloc_mtx`)

Locks a mutex and raises the current priority of the locking task to the ceiling priority of the mutex. When another task has already locked the mutex, the task that issued `loc_mtx` or `tloc_mtx` enters the WAITING state until the mutex is unlocked.

### (2) Locks Mutex (Polling) (`ploc_mtx`)

Locks a mutex and raises the current priority of the locking task to the ceiling priority of the mutex. The only difference between this service call and `loc_mtx` or `tloc_mtx` is that an error is immediately returned and the task that issued `ploc_mtx` does not enter the WAITING state when another task has already locked the mutex.

### (3) Unlocks Mutex (`unl_mtx`)

Unlocks a mutex. When issuing task have not locked another mutexes, the current priority of the task returns the base priority. When a task is waiting to lock the mutex, this service call makes the task leave the WAITING state.

### (4) Refers to Mutex Status (`ref_mtx`)

Refers to the state of a mutex, including the ID of a task that has locked the mutex and of waiting tasks.

### 4.9.1 Base Priority and Current Priority

A task has two priority levels: base priority and current priority. Tasks are scheduled according to current priority.

While a task does not have a mutex locked, its current priority is always the same as its base priority.

When a task locks a mutex, only its current priority is raised to the ceiling priority of the mutex.

When priority-changing service call `chg_pri` or `ichg_pri` is issued, both the base priority and current priority are changed if the specified task does not have a mutex locked. When the specified task locks a mutex, only the base priority is changed. When the specified task has a mutex locked or is waiting to lock a mutex, an `E_ILUSE` error is returned if a priority higher than the ceiling priority of the mutex is specified.

The current priority can be checked through service call `get_pri` or `iget_pri`.

## 4.10 Message Buffer

Like a mailbox, a message buffer is an object for the sending and receiving of messages, which are data with arbitrary size. The only difference is that the actual contents of the messages are copied and passed. For this reason, the message area becomes available immediately after a message has been sent, regardless of whether or not the receiving task has received the message.

Figure 4.13 shows the structure of a message buffer.

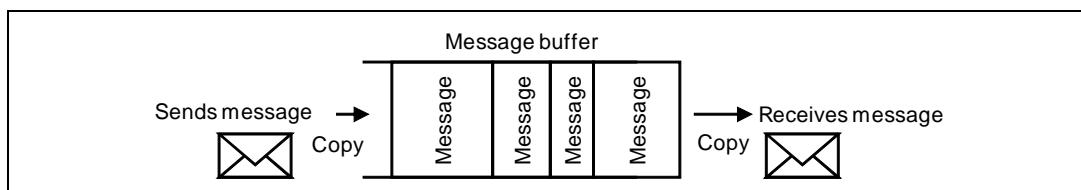


Figure 4.13 Message Buffer

Messages sent to a message buffer are stored in the buffer. When a message is received from a message buffer, the oldest message is taken out first (i.e. operation is FIFO).

Message buffers are controlled by the service calls listed below.

To create message buffers, writes "message\_buffer[]" in the cfg file. In the "message\_buffer[]" statement, following information are specified.

- ID name
- Buffer size
- Section name of the buffer area
- Maximum size of a message that can be transmitted

Message buffers are controlled by the service calls listed below.

### (1) Sends to Message Buffer (snd\_mbf, tsnd\_mbf)

Sends a message to a message buffer.

For a message to be sent to a message buffer, the message buffer must have at least the following amount of free space:

$$(\text{Size of the message in bytes rounded up to a multiple of 4}) + \text{VTSZ\_MBFTBL}$$

When the message buffer has less free space than is required, the task is in the WAITING state until enough space becomes available. This wait queue is managed in FIFO order.

**(2) Sends to Message Buffer (Polling) (psnd\_mbf, ipsnd\_mbf)**

Sends a message to a message buffer. The only difference between these service calls and `snd_mbf` or `tsnd_mbf` is that an error code is immediately returned and the task does not enter the `WAITING` state when the message buffer does not have enough free space.

**(3) Receives from Message Buffer (rcv\_mbf, trcv\_mbf)**

Receives a message from a message buffer. When the message buffer has no messages, the task enters the `WAITING` state until a message is sent to the message buffer. This wait queue is managed in `FIFO` order.

When a message is received from the message buffer, free space in the message buffer increases by the following amount:

(Size of the message in bytes rounded up to a multiple of 4) + `VTSZ_MBFTBL`

When the amount of free space in the message buffer becomes larger than the size of the message that a task is waiting to send, the message is sent to the message buffer and the task leaves the `WAITING` state.

**(4) Receives from Message Buffer (Polling) (prcv\_mbf)**

Receives a message from a message buffer. The only difference between this service call and `rcv_mbf` or `trcv_mbf` is that an error code is immediately returned and the task does not enter the `WAITING` state when the message buffer has no messages.

**(5) Refers to Message Buffer Status (ref\_mbf, iref\_mbf)**

Refers to the state of a message buffer, including the number of messages it contains, the amount of free space, and the IDs of tasks waiting to send or receive messages.

## 4.11 Fixed-sized Memory Pool

A fixed-sized memory pool is an object used to dynamically allocate and release memory blocks of fixed size. While fixed-sized memory pools cannot be used to acquire memory blocks of arbitrary size, their advantage over variable-sized memory pools is that acquiring and releasing blocks produces less overhead.

Figure 4.14 is a schematic view of a fixed-sized memory pool.

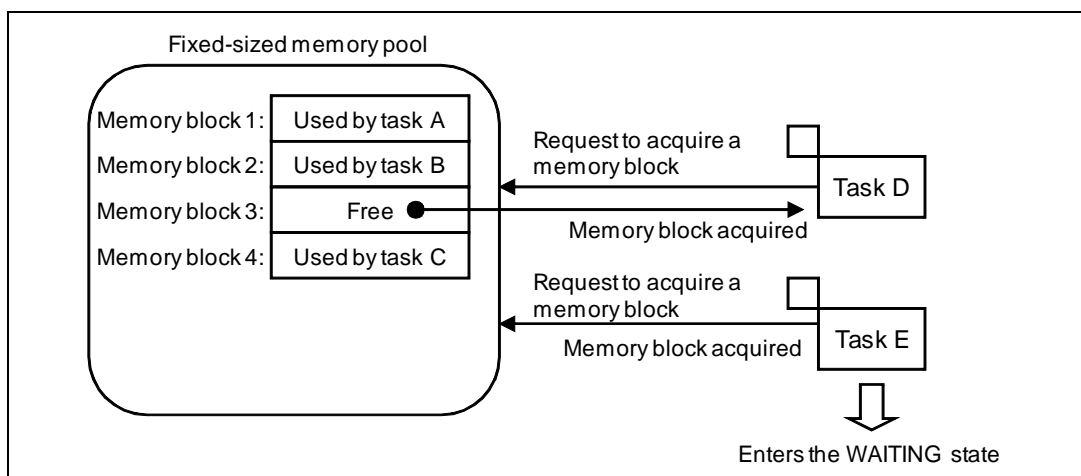


Figure 4.14 Fixed-sized Memory Pool

To create fixed-sized memory pools, writes "memorypool[]" in the cfg file. In the "memorypool[]" statement, following information are specified.

- ID name
- How tasks are queued waiting to acquire memory block  
TA\_TFIFO (queued in FIFO order) or TA\_TPRI (queued in order of task priority)
- Size of memory block
- Number of memory blocks
- Section name of the memory pool area

Control related to fixed-sized memory pools is implemented by the service calls listed below.

### (1) Gets Fixed-sized Memory Block (get\_mpf, tget\_mpf)

Acquires a fixed-sized memory block. When no memory block is available in the memory pool, the task enters the WAITING state until a memory block is released.

**(2) Gets Fixed-sized Memory Block (Polling) (pget\_mpf, ipget\_mpf)**

Acquires a fixed-sized memory block. The only difference between these service calls and get\_mpf or tget\_mpf is that an error code is immediately returned and the task does not enter the WAITING state when no memory blocks are available in the memory pool.

**(3) Releases Fixed-sized Memory Block (rel\_mpf, irel\_mpf)**

Releases a fixed-sized memory block. When a task is waiting to acquire a memory block, either service call makes the task leave the WAITING state.

**(4) Refers to Fixed-sized Memory Pool Status(ref\_mpf, iref\_mpf)**

Refers to the state of a fixed-sized memory pool, including the number of available memory blocks and the IDs of waiting tasks.

## 4.12 Variable-Sized Memory Pool

The variable-sized memory pool is an object that dynamically allocates and deallocates memory blocks of any size.

Compared to the fixed-sized memory pool, the variable-sized memory pool has the advantage that it can allocate memory blocks of any size, but there is a drawback to it in that it has large memory-acquiring/returning overhead. Furthermore, there is the problem associated with memory fragmentation, as will be described later.

When creating a variable-sized memory pool using the `cfg` file, be sure to specify the area in which to create the memory pool and its allocatable maximum size.

To create a variable-sized memory pool, write `variable_memorypool[]` in the `cfg` file. In `variable_memorypool[]`, specify the information listed below. Note that the memory acquisition queue is always managed in FIFO order.

- ID name
- Memory pool size
- Maximum size of the memory block acquirable
- Section name of the memory pool area

There are following service calls that manipulate the variable-sized memory pool

### (1) Gets Variable-sized Memory Block (`get_mpl`, `tget_mpl`)

Acquires a variable-sized memory block. When the variable-sized memory pool lacks the space for allocation of the memory block, the task enters the `WAITING` state until the memory pool has enough available space.

### (2) Gets Variable-sized Memory Block (Polling) (`pget_mpl`, `ipget_mpl`)

Acquires a variable-sized memory block. The only difference between these service calls and `get_mpl` or `tget_mpl` is that an error is immediately returned and the task does not enter the `WAITING` state when no memory block can be acquired from the memory pool.

### (3) Releases Variable-sized Memory Block (`rel_mpl`)

Releases a variable-sized memory block.

Releasing a memory block increases the amount of available space in the variable-sized memory pool. When a task has been waiting to acquire a block and the release of another block gives the memory pool enough available space, the task leaves the `WAITING` state and acquires the requested memory block.



#### (4) Refers to Variable-sized Memory Pool Status (ref\_mpl, iref\_mpl)

Refers to the state of a variable-sized memory pool, including the total amount of available memory, the maximum size of a contiguous memory block, and the IDs of waiting tasks.

### 4.12.1 About the Fragmentation of Free Spaces

As memory blocks are repeatedly acquired and freed (returned) from the variable-sized memory pool, the free spaces of memory will become fragmented, resulting in a situation where the total size of free spaces is adequate, but there are no contiguous free spaces, or a situation where it is impossible to acquire a large memory block (Figure 4.15).

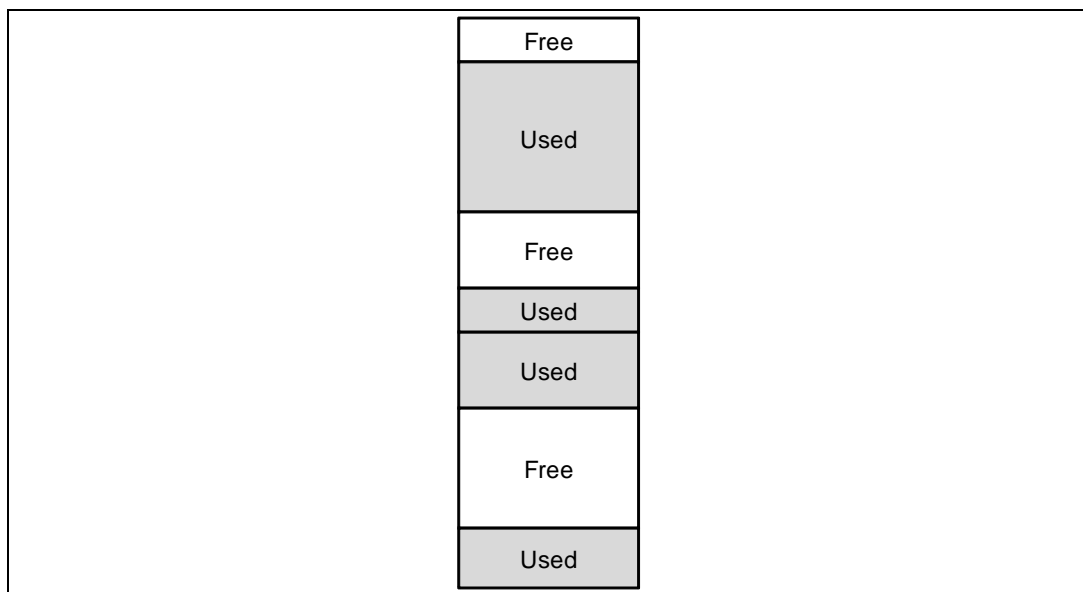


Figure 4.15 Fragmentation of Free Space

In this kernel, variations of memory block sizes are limited to make the memory less liable to become fragmented.

Variations of memory block sizes are determined based on `variable_memorypool[].max_memsize` in the `cfg` file. For details, refer to section 8.4.12, "Variable-sized Memory Pool Definition (`variable_memorypool[]`)."

## 4.13 Time Management Function

The kernel provides the following functions related to time management:

- Reference to and setting of the system clock
- Time event handler (cyclic handler and alarm handler) execution control
- Task execution control such as timeout

The unit of time used to define time parameters for the service calls is 1 [millisecond].

### 4.13.1 Task Timeout

Timeout values for WAITING states are specifiable with service calls that start with t, such as `tslp_tsk` and `twai_sem`.

When the wait condition has not been satisfied after the specified timeout period has elapsed, the task is taken out of the WAITING state and the error code `E_TMOUT` is returned as the return value for the service call.

Timeouts can be used to detect abnormal behavior in the form of events that should have been generated within the timeout period but were not.

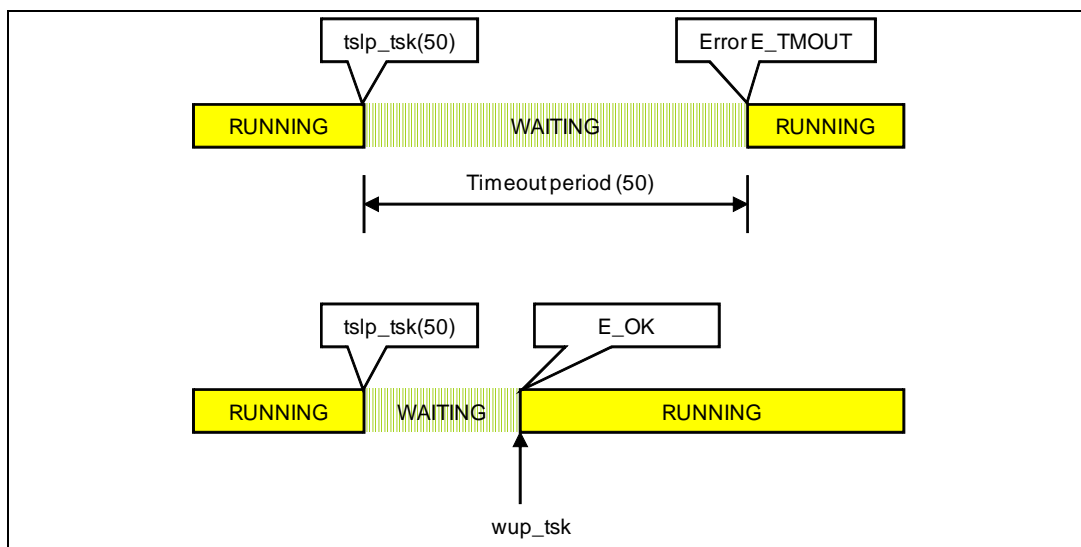


Figure 4.16 Timeout

### 4.13.2 Task Delay

Using `dly_tsk`, it is possible to place a task into a wait state for a specified duration of time. When the specified time elapses, the task is released from the wait state and `E_OK` is returned.

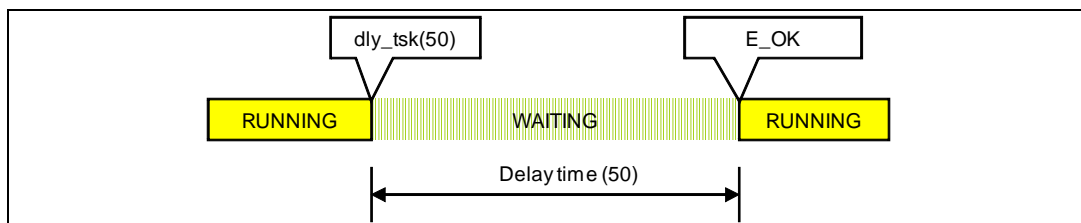


Figure 4.17 Task Delay

### 4.13.3 Cyclic Handler

The cyclic handler is a time event handler that is activated in each activation cycle after a specified activation phase has elapsed. There are two methods to activate the cyclic handler, in one of which the activation phase is saved and in the other the activation phase is not saved. In the former case, the cyclic handler activation time is determined relative to the time at which the cyclic handler was created (system startup time). In the latter case, the cyclic handler activation time is determined relative to the time at which the cyclic handler operation is started.

The cyclic handler has passed to it the extended information that was specified when it was created.

To generate a cyclic handler, write `cyclic_hand[]` in the `cfg` file. In `cyclic_hand[]`, specify the information listed below.

- ID name
- Cyclic handler start address
- Activation cycle
- Activation phase
- Whether to start operation (`TA_STA`) or not
- Whether to save the phase (`TA_PHS`) or not
- Extended information

Figure 4.18 and Figure 4.19 show examples of how the cyclic handler will operate.

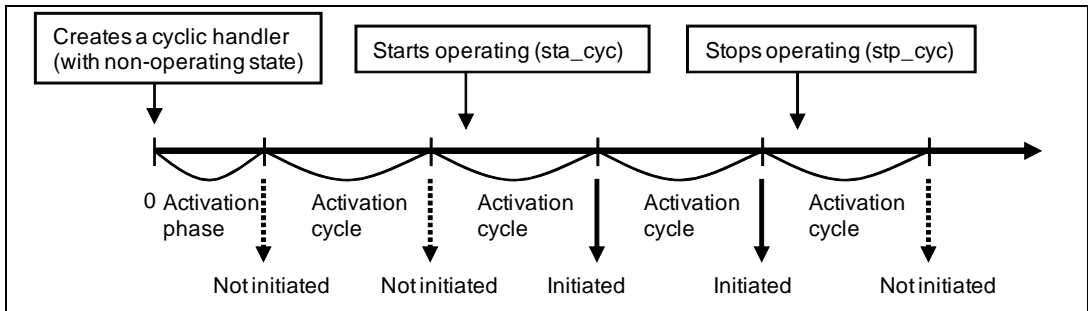


Figure 4.18 Examples of Cyclic Handler Operation (Save phase)

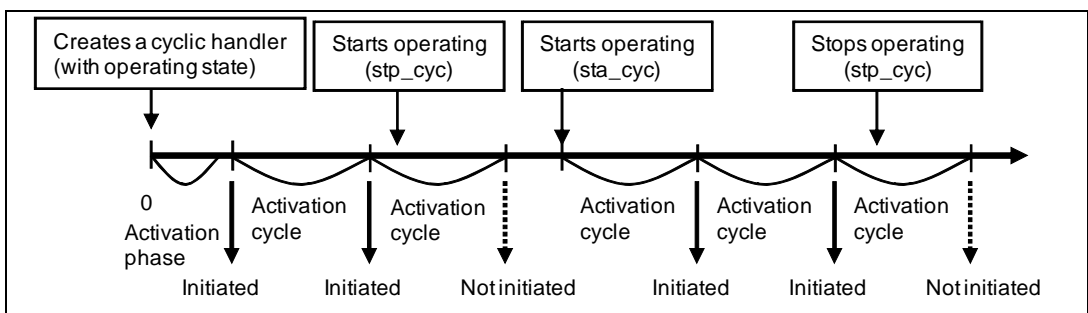


Figure 4.19 Examples of Cyclic Handler Operation (Not save phase)

Cyclic handlers are controlled by the service calls listed below.

**(1) Starts Cyclic Handler Operation (sta\_cyc, ista\_cyc)**

Starts a cyclic handler operation.

**(2) Stops Cyclic Handler Operation (stp\_cyc, istp\_cyc)**

Stops a cyclic handler operation.

**(3) Refers to Cyclic Handler Status (ref\_cyc, iref\_cyc)**

Refers to the operating state of the cyclic handler, including the time left until the cyclic handler is initiated.

### 4.13.4 Alarm Handler

The alarm handler is a time event handler that is activated only once when a specified time of day is reached. Using the alarm handler, it is possible to perform processing dependent on the time of day.

Figure 4.20 shows an example of how the alarm handler will operate.

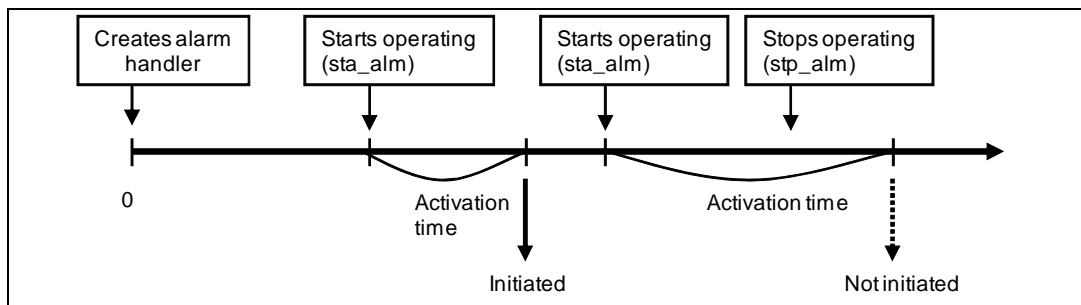


Figure 4.20 Example of Alarm Handler Operation

The alarm handler has passed to it the extended information that was specified when it was created.

To generate an alarm handler, write `alarm_hand[]` in the `cfg` file. In `alarm_hand[]`, specify the information listed below.

- ID name
- Alarm handler start address
- Extended Information

There are following service calls that manipulate the alarm handler.

#### (1) Starts Alarm Handler Operation (`sta_alm`, `ista_alm`)

Initiates an alarm handler after the specified time has elapsed.

#### (2) Stops Alarm Handler Operation (`stp_alm`, `istp_alm`)

Stops an alarm handler operation.

#### (3) Refers to Alarm Handler Status (`ref_alm`, `iref_alm`)

Refers to the operating status of the alarm handler and the time left until the alarm handler is initiated.

### 4.13.5 Accuracy of the Time

All of time-out and other time parameters are in millisecond units.

The accuracy of these items of time is  $TIC\_NUME / TIC\_DENO$  [ms]. Updating of the system time and the management of time are performed with this accuracy. Note that  $TIC\_NUME$  and  $TIC\_DENO$  are defined in `system.tic_nume` and `system.tic_deno` of the `cfg` file, respectively.

It is so designed that a time event (e.g., time-out occurrence or cyclic handler activation) will not occur before a specified relative time elapses.

Figure 4.21 shows examples where `tslp_tsk(5)` is executed at 9.2 [ms] in actual time.

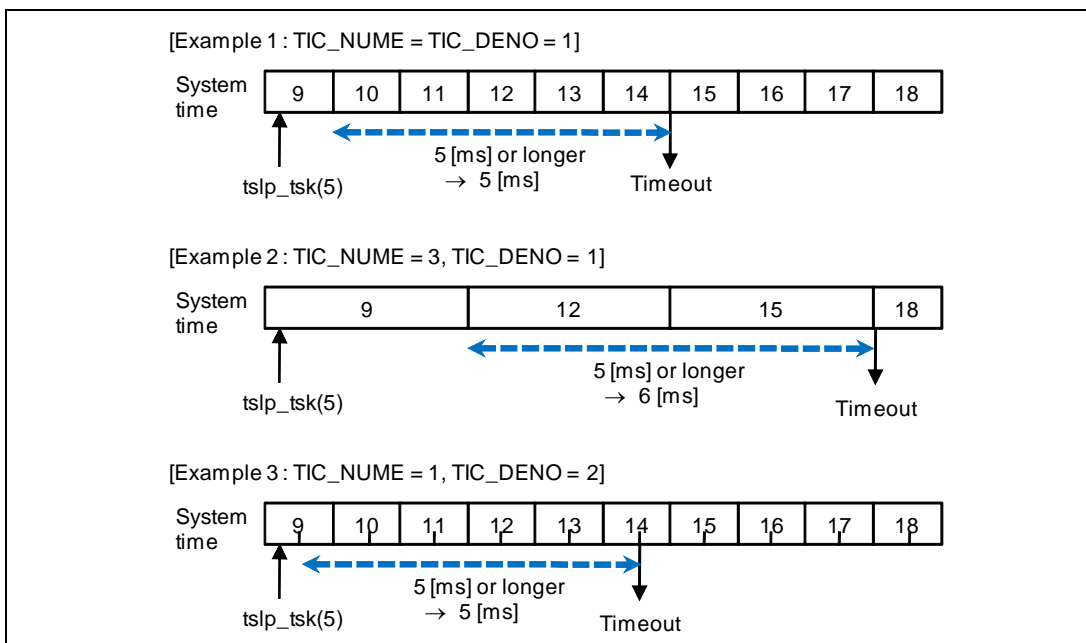


Figure 4.21 Accuracy of the Time (`tslp_tsk`)

For cyclic handlers, the relative time in each occurrence is handled as described below.

- (1) Cyclic handlers without `TA_PHS` attribute
  - (a) When operation starts in `sta_cyc` or `ista_cyc`  
The relative time in the  $n$ 'th occurrence, referenced to the `sta_cyc` or `ista_cyc` point of time, is handled as the value derived by the equation below.  
(activation cycle)  $\times$   $n$
  - (b) When operation starts after the `TA_STA` attribute is specified in the `cfg` file when the handler is generated

The relative time in the n'th occurrence, referenced to the system startup point of time (handler generation point of time), is handled as the value derived by the equation below.

$$(\text{activation phase}) + (\text{activation cycle}) \times (n - 1)$$

- (2) Cyclic handlers with TA\_PHS attribute  
(Handled the same way as in (b) of (1). However, whether the handler is actually activated depends on the handler's operating status.

### 4.13.6 Precautions

When a timer interrupt is generated, the kernel performs the processing described below.

- (a) Updates the system time
- (b) Activates and runs alarm handler
- (c) Activates and runs cyclic handler
- (d) Processes task timeout processing specified by service calls with the timeout function and dly\_tsk

These items of processing are all executed while the interrupts whose priority levels are below that of the timer interrupt (clock.IPL) are masked.

Of the above, (b), (c) and (d) could involve duplicate processing of multiple tasks or handlers, in which case the kernel's processing time may be extended by a huge amount of time. This will bring about the following adverse effects:

- Deteriorated responses to interrupts
- Delay in the system time

To avoid these, strictly observe the following:

- Reduce time event handler processing to the shortest time possible.
- Use as large values as possible for time event handler cycles and the time-out time specified in service calls with time-outs included. Think of an extreme case where a cyclic handler is assigned a cycle time of 1 ms, for example, and processing of the handler requires 1 ms or more. In such case, none but the cyclic handler alone will be executed forever, causing in effect the system to hang.

## 4.14 System State Management Function

### (1) Rotates Task Precedence (`rot_rdq`, `irotd_rdq`)

This service call establishes the time-sharing system (TSS). That is, rotating the ready queue at regular intervals accomplishes the round-robin scheduling required for the TSS.

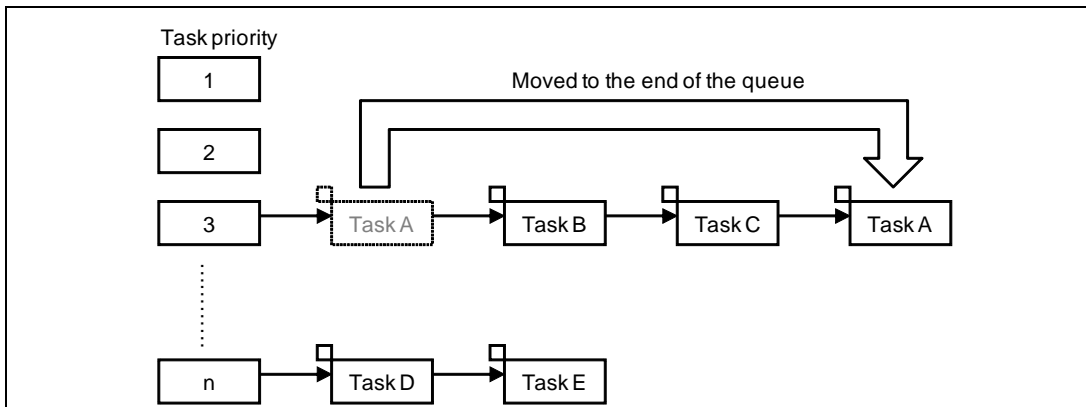


Figure 4.22 Operation of the Ready Queue by `rot_rdq`

### (2) Refers to Task ID in the RUNNING State (`get_tid`, `iget_tid`)

Refers to the ID of the task in the RUNNING state. When `iget_tid` is issued in a non-task context, the ID of the task running at the time is referred.

### (3) Locks the CPU (`loc_cpu`, `iloc_cpu`) and Unlocks the CPU (`unl_cpu`, `iunl_cpu`)

The `loc_cpu` or `iloc_cpu` makes the system enter the CPU-locked state. To subsequently leave the CPU-locked state, issue `unl_cpu` or `iunl_cpu`.

### (4) Disables Dispatching (`dis_dsp`) and Enables Dispatching (`ena_dsp`)

The `dis_dsp` makes the system enter the dispatching-disabled state. To subsequently leave the dispatching-disabled state, issue `ena_dsp`.

### (5) Refers to Context State (`sns_ctx`)

Checks whether the system is in a task or non-task context.

### (6) Refers to CPU-Locked State (`sns_loc`)

Checks whether the system is in the CPU-locked state or not.



**(7) Refers to Dispatching-Disabled State (sns\_dsp)**

Checks whether the system is in the dispatching-disabled state or not.

**(8) Refers to Dispatching-Pending State (sns\_dpn)**

Checks if the system is in the dispatching-pending state.

The dispatching-pending state means that processing with a higher priority than the dispatcher is in progress so that no other task can be executed. To be more specific, each of the following cases corresponds to the dispatching-pending state.

- CPU-locked state
- Dispatching-disabled state
- Non-task context

Unless the system is in the dispatch-pending state, all service calls to make a task enter the WAITING state are available. When developing software (e.g., middleware) that may be invoked from any system state, this service call (sns\_dpn) is useful for checking the current system state to see whether a service call that makes a task enter the WAITING state can be processed or will lead to an error being returned.

**(9) Starts Kernel (vsta\_knl, ivsta\_knl)**

Initiates the kernel according to the results of configuration.

**(10) System Down (vsys\_dwn, ivsys\_dwn)**

Makes the system go down and initiates the system-down routine.

## 4.15 Interrupt Management Function

When an interrupt is generated, the corresponding interrupt handler is initiated. Interrupt handlers should be defined through `interrupt_vector[]` (for relocatable-vector) or `interrupt_fvector[]` (for fixed-vector).

Also refer to section 3.7, "Interrupts."

### (1) Changes Interrupt Mask (`chg_ims`, `ichg_ims`)

Changes the interrupt mask (IPL bits in the PSW register) to the specified value.

In task-context, the system enters to dispatching-disabled state when the IPL bit is changed to other than 0, and the system enters to dispatching-enabled state when the IPL bit is changed to 0.

### (2) Refers to Interrupt Mask (`get_ims`, `iget_ims`)

Refers to the interrupt mask.

### (3) Returns from Kernel Interrupt Handler (`ret_int`)

Returns from a kernel interrupt handler.

The user don't have to describe calling `ret_int` because the code calls `ret_int` at the end of the interrupt handler is generated with the configuration.

## 4.16 System Configuration Management Function

### (1) Refers to Version Information (`ref_ver`, `iref_ver`)

Refers to the version numbers of the kernel and the  $\mu$ ITRON specification implemented in the kernel. The information acquired by `ref_ver` or `iref_ver` can also be acquired through kernel configuration macros (refer to section 5.23.2, "Content of Definition").

## 4.17 Object Reset Function

The object reset function initializes specified object.

This is the function outside  $\mu$ ITRON 4.0 specification.

### (1) Resets Data Queue (vrst\_dtq)

Resets a data queue. Tasks in waiting to send data are released from the WAITING state, and error EV\_RST is returned to the tasks. And data stored in the data queue is annulled.

### (2) Resets Mailbox (vrst\_mbx)

Resets a mailbox. Messages queued in the mailbox comes off from the management of the kernel.

### (3) Resets Message Buffer (vrst\_mbf)

Resets a message buffer. Tasks in waiting to send a message are released from the WAITING state, and error EV\_RST is returned to the tasks. And messages stored in the message buffer is annulled.

### (4) Resets Fixed-sized Memory Pool (vrst\_mpf)

Resets a fixed-sized memory pool. Tasks in waiting to acquire a memory block are released from the WAITING state, and error EV\_RST is returned to the tasks.

And memory blocks which has been allocated are handled as free space. Therefore, application program must not access the memory blocks which has been acquired after issuing this service call.

### (5) Resets Variable-sized Memory Pool (vrst\_mpl)

Resets a variable-sized memory pool. Tasks in waiting to acquire a memory block are released from the WAITING state, and error EV\_RST is returned to the tasks.

And memory blocks which has been allocated are handled as free space. Therefore, application program must not access the memory blocks which has been acquired after issuing this service call.

## 4.18 Kernel Idling

When there is no READY task, the kernel enters an endless loop and waits for interrupts.

The lowest-priority task is usually used to make transitions to low power consumption modes of the CPU.

## 5. Service Call Reference

### 5.1 Header File

In the application source, be sure to include kernel.h supplied by the RI600/4 and kernel\_id.h output by cfg600.

### 5.2 Basic Data Types

The basic data types are shown in Table 5.1.

Table 5.1 Basic Data Type

No.	Data Type	Meaning	No.	Data Type	Meaning
1	B	Signed 8-bit integer	18	ER	Signed 32-bit integer
2	H	Signed 16-bit integer	19	ID	Signed 16-bit integer
3	W	Signed 32-bit integer	20	ATR	Unsigned 16-bit integer
4	D	Signed 64-bit integer	21	STAT	Unsigned 16-bit integer
5	UB	Unsigned 8-bit integer	22	MODE	Unsigned 16-bit integer
6	UH	Unsigned 16-bit integer	23	PRI	Signed 16-bit integer
7	UW	Unsigned 32-bit integer	24	SIZE	Unsigned 32-bit integer
8	UD	Unsigned 64-bit integer	25	TMO	Signed 32-bit integer
9	VB	Signed 8-bit integer *	26	RELTIM	Unsigned 32-bit integer
10	VH	Signed 16-bit integer *	27	SYSTIM	A structure which contains the following members : Upper : Unsigned 16-bit integer Lower : Unsigned 32-bit integer
11	VW	Signed 32-bit integer *			
12	VD	Signed 64-bit integer *			
13	VP	Pointer to void data type	28	VP_INT	Signed 32-bit integer *
14	FP	Pointer to a function	29	ER_UINT	Signed 32-bit integer
15	INT	Signed 32-bit integer	30	FLGPTN	Unsigned 32-bit integer
16	UINT	Unsigned 32-bit integer	31	IMASK	Unsigned 16-bit integer
17	BOOL	Signed 32-bit integer			

Note: \* When the variable values of these data types are referred to or substituted, the type must be explicitly converted (casted).

## 5.3 Service Call Return Values and Error Codes

### 5.3.1 Summary

For service calls that have a return value, a positive value or 0 (E\_OK) means that the call is terminated normally, and a negative value represents error code. Although the value returned upon normal termination differs with each service call, most service calls return only E\_OK when they are terminated normally.

However, this does not apply to the service calls that have a BOOL-type return value.

### 5.3.2 Main Error Codes and Sub-Error Codes

The error code consists of the 8 low-order bits that constitute the main error code and the remaining other high-order bits that constitute sub-error code. The sub-error code in all error codes returned by this kernel is -1.

Note that the standard header `itron.h` has the following macros defined in it:

- ER MERCD (ER ercd) : Retrieves the main error code from error code
- ER SERCD (ER ercd) : Retrieves sub-code from error code
- ER ERCD (ER mercd, ER sercd) : Generates error code from the main error code and sub-error code

## 5.4 System Status and Service Calls

Whether a service call can be invoked depends on the system status.

### 5.4.1 Task Context and Non-Task Context

#### (1) Service calls beginning with sns

The service calls whose names begin with `sns` can be invoked from both task contexts and non-task contexts.

#### (2) Service calls other than (1)

The service calls that begin with `i` are non-task contexts only, and others are task contexts only.

Be aware that unless invoked in an enabled state, errors (E\_CTX error) may be or may not be detected depending on the service call concerned. For details, check for confirmation the error code column of each service call described later in this manual.

## 5.4.2 CPU-Locked State

The service calls that can be invoked from the CPU-locked state are limited to those that are listed below. If any other service call is invoked from the CPU-locked state, E\_CTX error is detected.

- ext\_tsk (released from the CPU-locked state)
- loc\_cpu, iloc\_cpu
- unl\_cpu, iunl\_cpu
- sns\_ctx
- sns\_loc
- sns\_dsp
- sns\_dpn
- vsta\_knl, ivsta\_knl
- vsys\_dwn, ivsys\_dwn

## 5.4.3 Dispatching-Disabled State

If a service call that transitions to a wait state is invoked, E\_CTX error is returned.

## 5.4.4 Non-Kernel Interrupt Handler, etc.

When the PSW.IPL is larger than the kernel interrupt mask level (system.system\_IPL), such as non-kernel interrupt handlers, do not call service calls<sup>2</sup>. If calling, the service call returns error E\_CTX. In this case, the PSW.IPL temporarily falls on the kernel interrupt mask level. Please use this error only for the purpose of debug.

## 5.5 Other Than $\mu$ ITRON Specification

The service calls whose names begin with the letter "v," "iv," or "V" as for the vrst\_dtq service call conform to this kernel's original specification other than  $\mu$ ITRON 4.0 specification.

Furthermore, the following "ixxx\_yyy" service calls (whose names begin with the letter "i") are the variations of  $\mu$ ITRON 4.0-compliant, task context-only "xxx\_yyy" service calls that have been made invocable from non-task contexts and are, therefore, not  $\mu$ ITRON 4.0 specification.

ista\_tsk, ichg\_pri, iget\_pri, iref\_tsk, iref\_tst, isus\_tsk, irsm\_tsk, ifrsm\_tsk, ipol\_sem, iref\_sem, iclr\_flg, ipol\_flg, iref\_flg, iprcv\_dtq, iref\_dtq, isnd\_mbx, iprcv\_mbx, iref\_mbx, ipsnd\_mbf, iref\_mbf, ipget\_mpf, irel\_mpf, iref\_mpf, ipget\_mpl, iref\_mpl, iset\_tim, iget\_tim, ista\_cyc, istp\_cyc, iref\_cyc, ista\_alm, istp\_alm, iref\_alm, ichg\_ims, iget\_ims, iref\_ver

<sup>2</sup> Except chg\_ims, ichg\_ims, get\_ims, iget\_ims, vsta\_knl, ivsta\_knl, vsys\_dwn, and ivsys\_dwn

## 5.6 Task Management Function

Table 5.2 shows specifications of the task management function.

Tasks are created by task[] definition in the cfg file.

Table 5.2 *Specifications of the Task Management Function*

No.	Item	Content
1	Task ID	1 - VTMAX_TSK *1
2	Task priority	1 - TMAX_TPRI *2
3	Maximum number of queued task activation request	255
4	Extension information (parameters passed to task)	32 bits
5	Task attribute	TA_HLNG : Written in high-level language *3 TA_ASM : Written in assembly language *3 TA_ACT : Activation attribute
6	Task stack	Assignable to each section separately

- Notes: 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of tasks defined in the cfg file.
- 2 This is the macro output to kernel\_id.h by cfg600, which represents the value specified in system.priority.
- 3 In the current implementation, there are no differences in task operation due to these attributes.

Table 5.3 *Service Calls for Task Management*

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	act_tsk	[S]	Activates task	√		√	√	√	
2	iact_tsk	[S]			√	√	√	√	
3	can_act	[S]	Cancels task activation requests	√		√	√	√	
4	ican_act				√	√	√	√	
5	sta_tsk	[B]	Activates task and specifies startup code	√		√	√	√	
6	ista_tsk				√	√	√	√	
7	ext_tsk	[S][B]	Terminates current task	√		√	√	√	√
8	ter_tsk	[S][B]	Terminates other task	√		√	√	√	
9	chg_pri	[S][B]	Changes task priority	√		√	√	√	
10	ichg_pri					√	√	√	√
11	get_pri	[S]	Refers task priority	√		√	√	√	
12	iget_pri					√	√	√	√
13	ref_tsk		Refers to task status	√		√	√	√	
14	iref_tsk					√	√	√	√
15	ref_tst		Refers to task status (simple version)	√		√	√	√	
16	iref_tst					√	√	√	√

- Notes: 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
- 2 The letters representing the system status have the following meanings:  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.6.1 Activates Task (act\_tsk, iact\_tsk)

### □ C Language API

```
ER ercd = act_tsk(ID tskid);
ER ercd = iact_tsk(ID tskid);
```

### □ Parameter

tskid      Task ID

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E\_ID                      Invalid ID number  
                               (1)tskid<0, VTMAX\_TSK < tskid  
                               (2)In an invocations from non-task context, tskid = TSK\_SELF (0)

E\_QOVR                    Queuing overflow (overflow of activate request queuing count)

E\_CTX                     Context error (invoked from an unallowed system state)

### □ Function

Activates the task indicated by tskid. The activated task transitions from the DORMANT state to the READY state. The processing performed at task activation is shown in Table 5.4.

Table 5.4 Processing Performed at Task Activation

No.	Content of processing
1	Initializes the task's base priority and current priority.
2	Clears the number of queued wakeup requests.
3	Clears the number of nested suspension count

In act\_tsk, specifying TSK\_SELF(0) means that the issuing task itself is specified.

The target task has passed as parameter to it the extension information for the task that was specified when it was created by using "task[]" in .cfg file.

When the task is not in the DORMANT state, up to 255 task activation requests from service calls act\_tsk and iact\_tsk can be queued.



## 5.6.2 Cancels Task Activation Request(`can_act`, `ican_act`)

### ❑ C Language API

```
ER_UINT actcnt = can_act(ID tskid);
ER_UINT actcnt = ican_act(ID tskid);
```

### ❑ Parameter

tskid      Task ID

### ❑ Return Value

Activation request count (positive value or 0), or error code

### ❑ Error Code

E_ID	Invalid ID number (1) <code>tskid &lt; 0</code> , <code>VTMAX_TSK &lt; tskid</code> (2) In an invocations from non-task context, <code>tskid = TSK_SELF (0)</code>
E_CTX	Context error (invoked from an unallowed system state) Note : The E_CTX is not detected in the following cases. (1) Invocation of <code>can_act</code> from non-task context (2) Invocation of <code>ican_act</code> from task context

### ❑ Function

Gets the number of activation requests that are queued for the task indicated by `tskid` and returns the result as return parameter, at the same time invalidating all of those activation requests.

In `can_act`, specifying `tskid = TSK_SELF(0)` means that the issuing task itself is specified.

This service call can be invoked for a task in the DORMANT state as the target. In that case, its return value is 0.

### 5.6.3 Activates Task with Start Code (sta\_tsk, ista\_tsk)

#### ❑ C Language API

```
ER ercd = sta_tsk(ID tskid, VP_INT stacd);  
ER ercd = ista_tsk(ID tskid, VP_INT stacd);
```

#### ❑ Parameter

tskid	Task ID
stacd	start code

#### ❑ Return Value

E\_OK for normal completion or error code

#### ❑ Error Code

E_ID	Invalid ID number (1)tskid<=0, VTMAX_TSK < tskid
E_OBJ	Object state error (task indicated by tskid is not in the DORMANT state)
E_CTX	Context error (invoked from an unallowed system state)

#### ❑ Function

Activates the task indicated by tskid. The activated task transitions from the DORMANT state to the READY state. At this time, the processing that needs to be executed at task activation time (see Table 5.4) is performed. The activated task has passed as parameter to it the task activation code that is indicated by stacd.

## 5.6.4 Terminates Current Task (ext\_tsk)

### □ C Language API

```
void ext_tsk(void);
```

### □ Return Value

Service calls ext\_tsk does not return to the position where it was issued.

When the following error is detected, the system will go down.

E\_CTX                      Context error (invoked from an unallowed system state)

### □ Function

The ext\_tsk service call terminates the issuing task normally. The task state changes from the RUNNING state to the DORMANT state. If activation requests are queued, the issuing task is temporarily terminated and then restarted. The processing performed at restart time is shown in Table 5.4.

The processing performed at task termination time is shown in Table 5.5.

Table 5.5 Processing Performed at Task Termination

No.	Content of processing
1	Unlocks the mutex that is locked by the task.

This service call does not have the function to automatically free the resources except the mutex hitherto occupied by the task (e.g., semaphores and memory blocks). Make sure the task frees these resources before it terminates.

This service call can be invoked from the dispatching-disabled or the CPU-locked state. In that case, the dispatching-disabled or the CPU-locked state is canceled.

Note that when the task returns from the entry function, the same operation as for service call ext\_tsk will be performed.

If this service call is invoked from non-task context or non-kernel interrupt handlers, an unrecoverable error is assumed and control jumps to the system-down routine.

## 5.6.5 Terminate Other Task (ter\_tsk)

### ❑ C Language API

```
ER ercd = ter_tsk(ID tskid);
```

### ❑ Parameter

tskid      Task ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)tskid<=0, VTMAX_TSK < tskid
E_OBJ	Object state error (task indicated by tskid is in the DORMANT state)
E_ILUSE	Illegal use of service call (task indicated by tskid is current task)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Forcibly terminates the other task indicated by tskid. The other task thus terminated transitions to the DORMANT state. At this time, the processing shown in Table 5.5 is performed.

If any activation request is queued, this service call performs the processing that needs to be executed at task activation time, as shown in Table 5.4, and places the target task into the READY state.

When the task waiting at the top of a message buffer send queue or a variable-sized memory pool memory acquisition queue is forcibly dequeued, it is possible that other tasks (waiting for message buffer transmission or variable-sized memory pool memory acquisition) will be released from the WAITING state.

This service call does not have the function to automatically free the resources except the mutex hitherto occupied by the task (e.g., semaphores and memory blocks). Make sure the task frees these resources before it terminates.

## 5.6.6 Changes Task Priority (chg\_pri, ichg\_pri)

### □ C Language API

```
ER ercd = chg_pri(ID tskid, PRI tskpri);
ER ercd = ichg_pri(ID tskid, PRI tskpri);
```

### □ Parameter

```
tskid      Task ID
tskpri     New base priority of the task
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error (1)tskpri < 0, TMAX_TPRI< tskpri
E_ID	Invalid ID number (1)tskid<0, VTMAX_TSK < tskid (2)In an invocations from non-task context, tskid = TSK_SELF (0)
E_ILUSE	Illegal use of service call(Ceiling priority is exceeded)
E_OBJ	Object state error (task indicated by tskid is in the DOERMANT state)
E_CTX	Context error (invoked from an unallowed system state)

### □ Function

Changes the base priority of the task indicated by tskid to the value indicated by tskpri.

In chg\_pri, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified.

Specifying tskpri = TPRI\_INI(0) causes the task's base priority to be reverted to its initial task priority that was specified when it was created (task[].priority).

The changed task base priority remains effective until the task terminates or this service call is invoked again. When the task goes to the DORMANT state, the task base priority it had before it terminated becomes null. The next time the task is activated, it assumes the initial task priority that was specified when it was created.

Also Changes the current priority of the task indicated by tskid to the value indicated by tskpri. But, the current priority is not changed when the target task has locked mutexes with TA\_CEILING attribute.

If the target task has locked mutexes with TA\_CEILING attribute or is waiting for mutex to be locked and if the task's base priority specified in tskpri is higher than the ceiling priority of the mutex, E\_ILUSE is returned.

## 5.6.7 Refers to Task Priority (get\_pri, iget\_pri)

### ❑ C Language API

```
ER ercd = get_pri(ID tskid, PRI *p_tskpri);
ER ercd = iget_pri(ID tskid, PRI *p_tskpri);
```

### ❑ Parameter

tskid	Task ID
p_tskpri	Pointer to storage to which the current priority of the target task is returned

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1) tskid < 0, VTMAX_TSK < tskid (2) In an invocations from non-task context, tskid = TSK_SELF (0)
E_OBJ	Object state error (task indicated by tskid is in the DORMANT state)
E_CTX	Context error (invoked from an unallowed system state) Note : The E_CTX is not detected in the following cases. (1) Invocation of get_pri from non-task context (2) Invocation of iget_pri from task context

### ❑ Function

Gets the current priority of the task indicated by tskid and returns it to the area pointed to by p\_tskpri.

In get\_pri, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified.

## 5.6.8 Refers to Task Status (ref\_tsk, iref\_tsk)

### □ C Language API

```
ER ercd = ref_tsk(ID tskid, T_RTsk *pk_rtsk);
ER ercd = iref_tsk(ID tskid, T_RTsk *pk_rtsk);
```

### □ Parameter

```
tskid      Task ID
pk_rtsk    Pointer to the storage to which the task state is returned
```

### □ Return Value

E\_OK for normal completion or error code

### □ Packet Structure

```
typedef struct {
    STAT  tskstat;      Task state
    PRI   tskpri;      Task current priority
    PRI   tskbpri;     Task base priority
    STAT  tskwait;     Reason for waiting
    ID    wobjid;      Object ID for which the task is waiting
    TMO   lefttmo;     Remaining time until timeout
    UINT  actcnt;      Activation request count
    UINT  wupcnt;      Wakeup request count
    UINT  suscnt;      Suspension count
} T_RTsk;
```

### □ Error Code

```
E_ID      Invalid ID number
          (1) tskid < 0, VTMAX_TSK < tskid
          (2) In an invocation from non-task context, tskid = TSK_SELF (0)
E_CTX     Context error (invoked from an unallowed system state)
          Note : The E_CTX is not detected in the following cases.
          (1) Invocation of ref_tsk from non-task context
          (2) Invocation of iref_tsk from task context
```

### □ Function

Refers to the status of the task indicated by tskid and returns it to the area pointed to by pk\_rtsk.

In ref\_tsk, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified.

The area pointed to by pk\_rtsk has one of the following values returned to it. Note that the data marked by an asterisk "\*" is indeterminate when the task is in the DORMANT state.

◆ **tskstat**

Current status of the task. One of the following values is returned in tskstat.

- TTS\_RUN (0x0001) : RUNNING state
- TTS\_RDY (0x0002) : READY state
- TTS\_WAI (0x0004) : WAITING state
- TTS\_SUS (0x0008) : SUSPENDED state
- TTS\_WAS (0x000c) : WAITING-SUSPENDED state
- TTS\_DMT (0x0010) : DORMANT state

◆ **tskpri**

Current priority of the task. If the task is in the DORMANT state, its initial priority is returned.

◆ **tskbpri**

Base priority of the task. If the task is in the DORMANT state, its initial priority is returned.

◆ **tskwait \***

Effective when tskstat = TTS\_WAI or TTS\_WAS, in which case one of the following values is returned.

- TTW\_SLP (0x0001) : WAITING state caused by slp\_tsk or tslp\_tsk
- TTW\_DLY (0x0002) : WAITING state caused by dly\_tsk
- TTW\_SEM (0x0004) : WAITING state caused by wai\_sem or twai\_sem
- TTW\_FLG (0x0008) : WAITING state caused by wai\_flg or twai\_flg
- TTW\_SDTQ (0x0010) : WAITING state caused by snd\_dtq or tsnd\_dtq
- TTW\_RDTQ (0x0020) : WAITING state caused by rcv\_dtq or trcv\_dtq
- TTW\_MBX (0x0040) : WAITING state caused by rcv\_mbx or trcv\_mbx
- TTW\_MTX (0x0080) : WAITING state caused by loc\_mtx or tloc\_mtx
- TTW\_SMBF (0x0100) : WAITING state caused by snd\_mbf or tsnd\_mbf
- TTW\_RMBF (0x0200) : WAITING state caused by rcv\_mbf or trcv\_mbf
- TTW\_MPF (0x2000) : WAITING state caused by get\_mpf or tget\_mpf
- TTW\_MPL (0x4000) : WAITING state caused by get\_mpl or tget\_mpl

◆ **wobjid \***

Effective when tskstat = TTS\_WAI or TTS\_WAS, in which case the target object ID waited for is returned.

◆ **lefttmo \***

If tskstat is TTS\_WAI or TTS\_WAS and if tskwait is other than TTW\_DLY, the remaining wait time of the target task is returned. If the time-out will be occurred at the next time-tick, 0 is returned.

For an endless wait, TMO\_FEVR is returned.

For TTW\_DLY (WAITING state by dly\_tsk), this return value is indeterminate.

◆ **actcnt**

The number of currently queued activation requests is returned.

◆ **wupcnt \***

The number of currently queued wakeup requests is returned.

◆ **suscnt \***

The number of currently nested suspension requests is returned.



## 5.6.9 Refers to Task Status (Simplified Version) (ref\_tst, iref\_tst)

### □ C Language API

```
ER ercd = ref_tst(ID tskid, T_RTST *pk_rtst);
ER ercd = iref_tst(ID tskid, T_RTST *pk_rtst);
```

### □ Parameter

```
tskid      Task ID
pk_rtst    Pointer to the storage to which the task state is returned
```

### □ Return Value

E\_OK for normal completion or error code

### □ Packet Structure

```
typedef struct {
    STAT  tskstat;    Task state
    STAT  tskwait;   Reason for waiting
} T_RTST;
```

### □ Error Code

```
E_ID          Invalid ID number
               (1) tskid < 0, VTMAX_TSK < tskid
               (2) In an invocation from non-task context, tskid = TSK_SELF (0)
E_CTX         Context error (invoked from an unallowed system state)
               Note : The E_CTX is not detected in the following cases.
                   (1) Invocation of ref_tst from non-task context
                   (2) Invocation of iref_tst from task context
```

### □ Function

Refers to the task status and the cause of wait regarding the task indicated by tskid and returns the result to the area pointed to by pk\_rtst.

In ref\_tst, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified.

The area pointed to by pk\_rtst has one of the following values returned to it. Note that the data marked by an asterisk "\*" is indeterminate when the task is in the DORMANT state.

#### ◆ tskstat

Current status of the task. One of the following values is returned in tskstat.

- TTS\_RUN (0x0001) : RUNNING state
- TTS\_RDY (0x0002) : READY state
- TTS\_WAI (0x0004) : WAITING state
- TTS\_SUS (0x0008) : SUSPENDED state
- TTS\_WAS (0x000c) : WAITING-SUSPENDED state
- TTS\_DMT (0x0010) : DORMANT state

◆ **tskwait \***

Effective when `tskstat = TTS_WAI` or `TTS_WAS`, in which case one of the following values is returned.

- `TTW_SLP (0x0001)` : WAITING state caused by `slp_tsk` or `tslp_tsk`
- `TTW_DLY (0x0002)` : WAITING state caused by `dly_tsk`
- `TTW_SEM (0x0004)` : WAITING state caused by `wai_sem` or `twai_sem`
- `TTW_FLG (0x0008)` : WAITING state caused by `wai_flg` or `twai_flg`
- `TTW_SDTQ (0x0010)` : WAITING state caused by `snd_dtq` or `tsnd_dtq`
- `TTW_RDTQ (0x0020)` : WAITING state caused by `rcv_dtq` or `trcv_dtq`
- `TTW_MBX (0x0040)` : WAITING state caused by `rcv_mbx` or `trcv_mbx`
- `TTW_MTX (0x0080)` : WAITING state caused by `loc_mtx` or `tloc_mtx`
- `TTW_SMBF (0x0100)` : WAITING state caused by `snd_mbf` or `tsnd_mbf`
- `TTW_RMBF (0x0200)` : WAITING state caused by `rcv_mbf` or `trcv_mbf`
- `TTW_MPF (0x2000)` : WAITING state caused by `get_mpf` or `tget_mpf`
- `TTW_MPL (0x4000)` : WAITING state caused by `get_mpl` or `tget_mpl`

## 5.7 Task Dependent Synchronization Function

Table 5.6 shows specifications of the task dependent synchronization function.

Table 5.6 Specifications of the Task Synchronization Function

No.	Item	Content
1	Maximum number of queued task wakeup request	255
2	Maximum number of nested task suspension request	1

Table 5.7 Service Calls for Task Dependent Synchronization

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	slp_tsk	[S][B]	Puts Task to Sleep	√		√		√	
2	tslp_tsk	[S]	Puts Task to Sleep (with Timeout)	√		√		√	
3	wup_tsk	[S][B]	Wakes up Task	√		√	√	√	
4	iwup_tsk	[S][B]			√	√	√	√	
5	can_wup	[S][B]	Cancels Task Wakeup Request	√		√	√	√	
6	ican_wup				√	√	√	√	
7	rel_wai	[S][B]	Release Task from WAITING State	√		√	√	√	
8	irel_wai	[S][B]			√	√	√	√	
9	sus_tsk	[S][B]	Suspend Task	√		√	√	√	
10	isus_tsk				√	√	√	√	
11	rsm_tsk	[S][B]	Resume Suspended Task	√		√	√	√	
12	irsm_tsk				√	√	√	√	
13	frsm_tsk	[S]	Forcibly Resume Suspended Task	√		√	√	√	
14	ifrsn_tsk				√	√	√	√	
15	dly_tsk	[S][B]	Delay Task	√		√		√	

- Notes: 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
- 2 The letters representing the system status have the following meanings :
- "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.7.1 Puts Task to Sleep (slp\_tsk, tslp\_tsk)

### ❑ C Language API

```
ER ercd = slp_tsk(void);
ER ercd = tslp_tsk(TMO tmout);
```

### ❑ Parameter

```
<Only for tslp_tsk>
tmout      Timeout (millisecond)
```

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_PAR	Parameter error (1) $tmout < -1$ , $(0x7FFFFFFF - TIC\_NUME) / TIC\_DENO < tmout$
E_TMOUT	Polling failure or timeout
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Places the issuing task into a wakeup wait state. However, if any wakeup request for the issuing task is queued, the number of queued wakeup requests is decremented by one and execution is continued as it is.

The task is released from the wakeup wait state by the wup\_tsk or iwup\_tsk service call. In this case, this service call is terminated normally.

For the tslp\_tsk service call, specify a wait time in tmout.

If a positive value is specified for tmout and the specified tmout time elapses while in the WAITING state, the task is placed out of the wait state and E\_TMOUT is returned as error code.

If, when  $tmout = TMO\_POL(0)$  is specified, the number of queued wakeup requests is greater than 0, the number of queued wakeup requests is decremented by 1 and execution is continued; if the number of queued requests is 0, E\_TMOUT is returned as error code.

If  $tmout = TMO\_FEVR(-1)$  is specified, time-outs are not watched. In this case, the tslp\_tsk service call operates the same way as slp\_tsk.

## 5.7.2 Wakeup Task (wup\_tsk, iwup\_tsk)

### ❑ C Language API

```
ER ercd = wup_tsk(ID tskid);  
ER ercd = iwup_tsk(ID tskid);
```

### ❑ Parameter

tskid      Task ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)tskid<0, VTMAX_TSK < tskid (2)In an invocations from non-task context, tskid = TSK_SELF (0)
E_OBJ	Object state error (task indicated by tskid is in the DORMANT state)
E_QOVR	Queuing overflow (overflow of wakeup request queuing count)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Releases the WAITING state by an invocation of the slp\_tsk or tslp\_tsk service call.

When the task is not in the WAITING state by an invocation of the slp\_tsk or tslp\_tsk service call, up to 255 task wakeup requests from service calls wup\_tsk and iwup\_tsk can be queued.

In wup\_tsk, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified.

### 5.7.3 Cancels Task Wakeup Request (can\_wup, ican\_wup)

#### ❑ C Language API

```
ER_UINT wupcnt = can_wup(ID tskid);
ER_UINT wupcnt = ican_wup(ID tskid);
```

#### ❑ Parameter

tskid      Task ID

#### ❑ Return Value

Wakeup request count (positive value or 0), or error code

#### ❑ Error Code

E_ID	Invalid ID number (1)tskid<0, VTMAX_TSK < tskid (2)In an invocations from non-task context, tskid = TSK_SELF (0)
E_OBJ	Object state error (task indicated by tskid is in the DORMANT state)
E_CTX	Context error (invoked from an unallowed system state) Note : The E_CTX is not detected in the following cases. (1) Invocation of can_wup from non-task context (2) Invocation of ican_wup from task context

#### ❑ Function

Gets a count of wakeup requests that have been queued in the task indicated by tskid and returns the result as return parameter, at the same time invalidating all of those wakeup requests.

In can\_wup, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified.

## 5.7.4 Releases Task from WAITING State (rel\_wai, irel\_wai)

### ❑ C Language API

```
ER ercd = rel_wai(ID tskid);
ER ercd = irel_wai(ID tskid);
```

### ❑ Parameter

tskid      Task ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)tskid<=0, VTMAX_TSK < tskid
E_OBJ	Object state error (Task indicated by tskid is not in the WAITING state)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

If the task indicated by tskid is in some kind of WAITING state (except the SUSPENDED state), this service call forcibly releases the WAITING state. The task freed by this service call has E\_RLWAI returned to it as error code.

If this service call is invoked for a task that is in the WAITING-SUSPENDED state, the target task goes to the SUSPENDED state. Then, when the rsm\_tsk or irsm\_tsk, or the frsm\_tsk or ifrsm\_tsk service call is invoked, the target task is released from the SUSPENDED state, in which case the task has E\_RLWAI returned to it as error code.

When the task at the top of a message buffer send queue or a variable-sized memory pool memory acquisition queue is forcibly dequeued, it is possible that other tasks (waiting for message buffer transmission or variable-sized memory pool memory acquisition) will be released from the wait state.

To release tasks from the SUSPENDED state, use rsm\_tsk, irsm\_tsk, frsm\_tsk, or ifrsm\_tsk.

## 5.7.5 Suspends Task (sus\_tsk, isus\_tsk)

### ❑ C Language API

```
ER ercd = sus_tsk(ID tskid);
ER ercd = isus_tsk(ID tskid);
```

### ❑ Parameter

tskid      Task ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)tskid<0, VTMAX_TSK < tskid (2)In an invocations from non-task context, tskid = TSK_SELF (0)
E_OBJ	Object state error (task indicated by tskid is in the DORMANT state)
E_QOVR	Queuing overflow (overflow of suspension request nesting count)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Suspends execution of the task indicated by tskid and places it into the SUSPENDED state. If the task indicated by tskid is in the WAITING state when this service call is invoked, it goes to the WAITING-SUSPENDED state. At this time, the number of nested suspension requests changes from 0 to 1. If the target task is already in the SUSPENDED state or WAITING-SUSPENDED state, error E\_QOVR is returned. At this time, the number of nested suspension requests remains unchanged (= 1). This is because the number of nested suspension requests by this service call is 1 at the most.

In sus\_tsk, specifying tskid = TSK\_SELF(0) means that the issuing task itself is specified. However, if, while in a dispatching-disabled state, TSK\_SELF or the issuing task ID is specified for tskid when the sus\_tsk service call is invoked, error E\_CTX is returned.

Tasks are released from the SUSPENDED state by an invocation of the rsm\_tsk, irsm\_tsk, frsm\_tsk or ifrsm\_tsk service call.



## 5.7.6 Resumes Suspended Task (rsm\_tsk, irsm\_tsk), Forcibly Resumes Suspended Task (frsm\_tsk, ifrsm\_tsk)

### ❑ C Language API

```
ER ercd = rsm_tsk(ID tskid);
ER ercd = irsm_tsk(ID tskid);
ER ercd = frsm_tsk(ID tskid);
ER ercd = ifrsm_tsk(ID tskid);
```

### ❑ Parameter

tskid      Task ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)tskid<=0, VTMAX_TSK < tskid
E_OBJ	Object state error (task indicated by tskid is not in the SUSPENDED state)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Releases the task indicated by tskid from the SUSPENDED state.

More specifically, the rsm\_tsk and irsm\_tsk service calls operate in such a way that if the task indicated by tskid is in the SUSPENDED state when either call is invoked, the number of nested suspension requests is decremented by 1. Since the number of nested suspension requests is 1 at the most, the number of nested suspension requests is thereby decremented to 0, resulting in the SUSPENDED being removed.

The frsm\_tsk and ifrsm\_tsk service calls decrement the number of nested suspension requests to 0. In this kernel, since the number of nested suspension requests is 1 at the most, these service calls behave the same way as rsm\_tsk and irsm\_tsk.

## 5.7.7 Delays Task (dly\_tsk)

### ❑ C Language API

```
ER ercd = dly_tsk(RELTIM dlytim);
```

### ❑ Parameter

dlytim      Delayed time

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_PAR	Parameter error (1) $(0x7FFFFFFF - TIC\_NUME) / TIC\_DENO < dlytim$
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Changes the status of the issuing task from an execution state to a lapse of time wait state, waiting for the time specified by dlytim to elapse. When the time specified by dlytim has elapsed, the status of the issuing task is changed back to the READY state. If dlytim = 0 is specified and in this case too, the issuing task is placed into the WAITING state.

This service call, unlike the tslp\_tsk service call, is terminated normally when it has finished off by delaying execution by an amount of time, dlytim. Note also that even when the wup\_tsk or iwup\_tsk service call is executed during the delay time, the wait state is not exited. It is only when the rel\_wai, irel\_wai or the ter\_tsk service call is invoked that the wait state is exited before the delay time elapses.

## 5.8 Synchronization and Communication Function (Semaphore)

Table 5.8 shows specifications of the semaphore function.

Semaphores are created by semaphore[] definition in the cfg file.

Table 5.8 Specifications of the Semaphore Function

No.	Item	Content
1	Semaphore ID	1 - VTMAX_SEM *1
2	Maximum semaphore count	1 - TMAX_MAXSEM *2
3	Semaphore attributes	TA_TFIFO : Wait task queue is managed in FIFO order TA_TPRI : Wait task queue is managed in order of task priority

- Notes: 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of semaphores defined in the cfg file.  
2 This is the macro defined in kernel.h. The definition is 65535.

Table 5.9 Service Calls for Semaphore Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	sig_sem	[S][B]	Releases Semaphore Resource	√		√	√	√	
2	isig_sem	[S][B]			√	√	√	√	
3	wai_sem	[S][B]	Acquire Semaphore Resource	√		√		√	
4	pol_sem	[S][B]	Acquire Semaphore Resource (Polling)	√		√	√	√	
5	ipol_sem					√	√	√	√
6	twai_sem		Acquire Semaphore Resource (with Timeout)	√		√		√	
7	ref_sem	[S]	Refers to Semaphore Status	√		√	√	√	
8	iref_sem					√	√	√	√

- Notes: 1 The symbol "[S]" denotes  $\mu$ ITRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ ITRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ ITRON 4.0 specification.  
2 The letters representing the system status have the following meanings :  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.8.1 Releases Semaphore Resource (sig\_sem, isig\_sem)

### □ C Language API

```
ER ercd = sig_sem(ID semid);  
ER ercd = isig_sem(ID semid);
```

### □ Parameter

semid      Semaphore ID

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_ID	Invalid ID number (1)semid<=0, VTMAX_SEM < semid
E_QOVR	Queuing overflow (overflow of semaphore count)
E_CTX	Context error (invoked from an unallowed system state)

### □ Function

Returns one resource to the semaphore indicated by semid. If the target semaphore has any task waiting for it, the task at the top of the semaphore queue is assigned the resource, upon which the task is dequeued. If there are no tasks waiting for the semaphore, the count value of the semaphore is incremented by 1.

Note that the maximum value of the semaphore count is defined in semaphore[].max\_count.

## 5.8.2 Acquires Semaphore Resource (wai\_sem, pol\_sem, ipol\_sem, twai\_sem)

### □ C Language API

```
ER ercd = wai_sem(ID semid);
ER ercd = pol_sem(ID semid);
ER ercd = ipol_sem(ID semid);
ER ercd = twai_sem(ID semid, TMO tmout);
```

### □ Parameter

```
semid      Semaphore ID
<Only for twai_sem>
tmout      Timeout (millisecond)
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error (1) $tmout < -1$ , $(0x7FFFFFFF - TIC\_NUME) / TIC\_DENO < tmout$
E_ID	Invalid ID number (1) $semid \leq 0$ , $VTMAX\_SEM < semid$
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT	Polling failure or timeout
E_CTX	Context error (invoked from an unallowed system state Note : The E_CTX is not detected in the following cases. (1) Invocation of pol_sem from non-task context (2) Invocation of ipol_sem from task context

### □ Function

Acquires one resource from the semaphore indicated by semid.

If the target semaphore has 1 or more resources, the number of resources of the semaphore is decremented by 1 and execution is continued. If the number of resource is 0 and the service call concerned is wai\_sem or twai\_sem, then the invoking task is tied to the semaphore queue; or, in the case of the pol\_sem or ipol\_sem service call, it immediately returns error E\_TMOUT. The queue is managed according to the attributes specified when the semaphore was created.

For the twai\_sem service call, specify a wait time in tmout. If a positive value is specified for tmout and the specified tmout time elapses while the wait release condition remains unmet, E\_TMOUT is returned as error code. If  $tmout = TMO\_POL(0)$  is specified, the service call is processed in the same way as with pol\_sem. If  $tmout = TMO\_FEVR(-1)$  is specified, time-outs are not watched. In this case, the service call operates the same way as with wai\_sem.

### 5.8.3 Refers to Semaphore Status (ref\_sem, iref\_sem)

#### □ C Language API

```
ER ercd = ref_sem(ID semid, T_RSEM *pk_rsem);
ER ercd = iref_sem(ID semid, T_RSEM *pk_rsem);
```

#### □ Parameter

```
semid      Semaphore ID
pk_rsem    Pointer to the storage to which the semaphore state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    ID      wtskid;      The task ID at the top of the task wait queue
    UINT    semcnt;     Current semaphore count
} T_RSEM;
```

#### □ Error Code

```
E_ID      Invalid ID number
           (1) semid <= 0, VTMAX_SEM < semid
E_CTX     Context error (invoked from an unallowed system state)
           Note : The E_CTX is not detected in the following cases.
           (1) Invocation of ref_sem from non-task context
           (2) Invocation of iref_sem from task context
```

#### □ Function

Refers to the status of the semaphore indicated by semid.

The area pointed to by pk\_rsem will have returned to it the task ID at the top of the queue (wtskid) and the current semaphore count value (semcnt).

If the target semaphore has no tasks waiting for it, TSK\_NONE(0) is returned as the waiting task ID.

## 5.9 Synchronization and Communication Function (Eventflag)

Table 5.10 shows specifications of the eventflag function.

Eventflags are created by flag[] definition in the cfg file.

Table 5.10 Specifications of the Eventflag Function

No.	Item	Content
1	Eventflag ID	1 - VTMAX_FLG *1
2	Eventflag size	32 bits
3	Eventflag attribute	TA_TFIFO : Wait task queue is managed in FIFO order TA_TPRI : Wait task queue is managed in order of task priority *2 TA_WSGL : Does not permit multiple tasks to wait for the eventflag TA_WMUL : Permits multiple tasks to wait for the eventflag TA_CLR : Clears the eventflag at the time of waiting release

- Notes:
- 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of eventflags defined in the cfg file.
  - 2 If TA\_CLR attribute is not specified, even if there is the TA\_TPRI attribute specified, the queue is managed in the same way as for the TA\_TFIFO attribute. This behavior falls outside  $\mu$ ITRON 4.0 specification.

Table 5.11 Service Calls for Eventflag Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	set_flg	[S][B]	Sets eventflag	√		√	√	√	
2	iset_flg	[S][B]			√	√	√	√	
3	clr_flg	[S][B]	Clears eventflag	√		√	√	√	
4	iclr_flg				√	√	√	√	
5	wai_flg	[S][B]	Waits for eventflag	√		√		√	
6	pol_flg	[S][B]	Waits for eventflag (Polling)	√		√	√	√	
7	ipol_flg	[S]				√	√	√	
8	twai_flg	[S]	Waits for eventflag (with Timeout)	√		√		√	
9	ref_flg		Refers to eventflag status	√		√	√	√	
10	iref_flg					√	√	√	√

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ ITRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ ITRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ ITRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings :  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.9.1 Sets Eventflag (set\_flg, iset\_flg)

### □ C Language API

```
ER ercd = set_flg(ID flgid, FLGPTN setptn);
ER ercd = iset_flg(ID flgid, FLGPTN setptn);
```

### □ Parameter

```
flgid      Eventflag ID
setptn     Bit pattern to set
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

```
E_ID          Invalid ID number
              (1) flgid <= 0, VTMAX_FLG < flgid
E_CTX         Context error (invoked from an unallowed system state)
```

### □ Function

Updates the eventflag indicated by flgid to the one logically OR'ed with the value indicated by setptn.

If updating of the eventflag value results in the wait release condition for tasks in the wait task queue being satisfied, the tasks are released from the WAITING state. Note that the wait release conditions of each waiting task are evaluated in order of the wait task queue. At this time, if the target eventflag has TA\_CLR attribute specified, all bits in the eventflag's bit pattern are cleared and the service call has its processing thereby finished.

If the eventflag has the TA\_WMUL attribute specified but does not have the TA\_CLR attribute specified, it is possible that multiple tasks will be released from the WAITING states by one invocation of set\_flg. If there are multiple tasks to be released from the WAITING states, they are freed in the order they are tied up in the task wait queue.



## 5.9.2 Clears Eventflag (clr\_flg, iclr\_flg)

### ❑ C Language API

```
ER ercd = clr_flg(ID flgid, FLGPTN clrptn);  
ER ercd = iclr_flg(ID flgid, FLGPTN clrptn);
```

### ❑ Parameter

flgid      Eventflag ID  
clrptn     Bit pattern to clear

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E\_ID                    Invalid ID number  
                          (1) flgid <= 0, VTMAX\_FLG < flgid  
  
E\_CTX                   Context error (invoked from an unallowed system state)  
                          Note : The E\_CTX is not detected in the following cases.  
                          (1) Invocation of clr\_flg from non-task context  
                          (2) Invocation of iclr\_flg from task context

### ❑ Function

Updates the eventflag indicated by flgid to the one logically AND'ed with the value indicated by clrptn.  
If the bits of clrptn are all 1's, no operation will be performed on the eventflag, but no errors are assumed.

### 5.9.3 Waits for Eventflag (wai\_flg, pol\_flg, ipol\_flg, twai\_flg)

#### □ C Language API

```
ER ercd = wai_flg(ID flgid, FLGPTN waiptn, MODE wfmode, FLGPTN *p_flgptn);
ER ercd = pol_flg(ID flgid, FLGPTN waiptn, MODE wfmode, FLGPTN *p_flgptn);
ER ercd = ipol_flg(ID flgid, FLGPTN waiptn, MODE wfmode, FLGPTN *p_flgptn);
ER ercd = twai_flg(ID flgid, FLGPTN waiptn, MODE wfmode, FLGPTN *p_flgptn, TMO tmout);
```

#### □ Parameter

```
flgid      Eventflag ID
waiptn     Wait bit pattern
wfmode     Wait mode
p_flgptn   Pointer to the storage to which the bit pattern at waiting release is
           returned
<Only for twai_flg>
tmout      Timeout (millisecond)
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Error Code

```
E_PAR      Parameter error
           (1) waiptn=0
           (2) wfmode is invalid
           (3) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID       Invalid ID number
           (1) flgid<=0, VTMAX_FLG < flgid
E_ILUSE    Illegal use of service call(a task is already waiting for the
           eventflag with TA_WSGL attribute)
E_RLWAI    Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT    Polling failure or timeout
E_CTX      Context error (invoked from an unallowed system state)
           Note : The E_CTX is not detected in the following cases.
           (1) Invocation of pol_flg from non-task context
           (2) Invocation of ipol_flg from task context
```

#### □ Function

Waits for the bit pattern of the eventflag indicated by flgid to satisfy the wait release condition specified by waiptn and wfmode. The area pointed to by p\_flgptn will have returned to it the eventflag bit pattern that satisfied the above condition.

If, when this service call is invoked, the wait release condition is already met, the service call is immediately completed. If the wait release condition is not met yet and the service call concerned is wai\_flg or twai\_flg, the task is tied to the task wait queue; or, in the case of the pol\_flg and ipol\_flg service calls, it immediately returns error E\_TMOUT.

If TA\_TFIFO attribute is specified when created, the queue is managed in FIFO order.

On the other hand, if TA\_TPRI attribute is specified, the queue is managed in order of task priority. Among tasks with the same priority, the queue is managed in FIFO order.

However, if TA\_CLR attribute is not specified, even if there is the TA\_TPRI attribute specified, the queue is managed in the same way as for the TA\_TFIFO attribute. This behavior falls outside  $\mu$ ITRON 4.0 specification.

Note that if TA\_WSGL attribute is specified, because in no case can multiple tasks wait for an eventflag at the same time, no differences exist between TA\_TFIFO and TA\_TPRI.

For wfmode, specify as follows :

wfmode : = ( (TWF\_ANDW | TWF\_ORW) )

- TWF\_ANDW (0x00000000) : AND wait
- TWF\_ORW (0x00000001) : OR wait

For TWF\_ANDW, the service call waits for all of the bits specified by waiptrn to be set. For TWF\_ORW, the service call waits for one of the bits specified by waiptrn in the eventflag indicated by flgid to be set.

For the twai\_flg service call, specify a wait time in tmout. If a positive value is specified for tmout and the specified tmout time elapses while the wait condition remains unmet, E\_TMOUT is returned as error code. If tmout = TMO\_POL(0) is specified, the service call is processed in the same way as with pol\_flg. If tmout = TMO\_FEVR(-1) is specified, time-outs are not watched. In this case, the service call operates the same way as with wai\_flg.

## 5.9.4 Refers to Eventflag Status (ref\_flg, iref\_flg)

### □ C Language API

```
ER ercd = ref_flg(ID flgid, T_RFLG *pk_rflg);
ER ercd = iref_flg(ID flgid, T_RFLG *pk_rflg);
```

### □ Parameter

```
flgid      Eventflag ID
pk_rflg    Pointer to the storage to which the eventflag state is returned
```

### □ Return Value

E\_OK for normal completion or error code

### □ Packet Structure

```
typedef struct {
    ID      wtskid;      The task ID at the top of the task wait queue
    FLGPTN flgptn;      Evetnflag's current bit pattern
} T_RFLG;
```

### □ Error Code

```
E_ID          Invalid ID number
              (1) flgid <= 0, VTMAX_FLG < flgid
E_CTX         Context error (invoked from an unallowed system state)
              Note : The E_CTX is not detected in the following cases.
                  (1) Invocation of ref_flg from non-task context
                  (2) Invocation of iref_flg from task context
```

### □ Function

Refers to the status of the eventflag indicated by flgid.

The area pointed to by pk\_rflg will have the task ID at the top of the queue (wtskid) and the current bit pattern of the eventflag (flgptn) returned to it.

If there are no tasks waiting for the target eventflag, TSK\_NONE(0) is returned as the waiting task ID.

## 5.10 Synchronization and Communication Function (Data Queue)

Table 5.12 shows specifications of the data queue function.

Data queues are created by dataqueue[] definition in the cfg file.

Table 5.12 Specifications of the Data Queue Function

No.	Item	Content
1	Data queue ID	1 - VTMAX_DTQ *1
2	Data size	4 bytes
3	Data queue attribute	TA_TFIFO : Wait task queue for sending is managed in FIFO order TA_TPRI : Wait task queue for sending is managed in order of task priority

Notes: 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of data queues defined in the cfg file.

Table 5.13 Service Calls for Data Queue Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	snd_dtq	[S]	Sends to data queue	√		√		√	
2	psnd_dtq	[S]	Sends to data queue (Polling)	√		√	√	√	
3	ipsnd_dtq	[S]			√	√	√	√	
4	tsnd_dtq	[S]	Sends to data queue (with Timeout)	√		√		√	
5	fsnd_dtq	[S]	Forced sends to data queue	√		√	√	√	
6	ifsnd_dtq	[S]			√	√	√	√	
7	rcv_dtq	[S]	Receives from data queue	√		√		√	
8	prcv_dtq	[S]	Receives from data queue (Polling)	√		√	√	√	
9	iprcv_dtq				√	√	√	√	
10	trcv_dtq	[S]	Receives from data queue (with Timeout)	√		√		√	
11	ref_dtq		Refers to data queue status	√		√	√	√	
12	iref_dtq				√	√	√	√	

Notes: 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.

2 The letters representing the system status have the following meanings :  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.10.1 Sends to Data Queue (snd\_dtq,psnd\_dtq,ipsnd\_dtq,tsnd\_dtq,fsnd\_dtq, ifsnd\_dtq)

### □ C Language API

```
ER ercd = snd_dtq(ID dtqid, VP_INT data);
ER ercd = psnd_dtq(ID dtqid, VP_INT data);
ER ercd = ipsnd_dtq(ID dtqid, VP_INT data);
ER ercd = tsnd_dtq(ID dtqid, VP_INT data, TMO tmout);
ER ercd = fsnd_dtq(ID dtqid, VP_INT data);
ER ercd = ifsnd_dtq(ID dtqid, VP_INT data);
```

### □ Parameter

```
dtqid      Data queue ID
data       Data to be sent
<Only for tsnd_dtq>
tmout      Timeout (millisecond)
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error (1) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID	Invalid ID number (1) dtqid <= 0, VTMAX_DTQ < dtqid
E_ILUSE	Illegal use of service call (fsnd_dtq or ifsnd_dtq is issued for the data queue which dtqcnt is 0)
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT	Polling failure or timeout
E_CTX	Context error (invoked from an unallowed system state)
EV_RST	Released from WAITING state by the object reset (vrst_dtq)

## □ Function

Sends the data indicated by data (4 bytes) to the data queue indicated by dtqid.

For fsnd\_dtq and ifsnd\_dtq, note that if a data queue created with dtqcnt = 0 is specified, the call always results in E\_ILUSE error.

### (1) If the target data queue contains any task waiting to receive

The data is not stored in the data queue, but instead passed to the task at the top of the receive queue, upon which the task is dequeued.

### (2) If the target data queue contains no tasks waiting to receive

#### (a) When the data queue has space

The data is stored in the tail end of the data queue and the data queue count is incremented by 1.

#### (b) When the data queue has no space

- For snd\_dtq and tsnd\_dtq

The invoking task is tied to a queue (send queue) to wait for space to be created in the data queue. For the tsnd\_dtq service call, specify a wait time in tmout. If a positive value is specified for tmout and the specified tmout time elapses while the wait condition remains unmet, E\_TMOUT is returned as error code. If tmout = TMO\_POL(0) is specified, the service call is processed in the same way as with psnd\_dtq. If tmout = TMO\_FEVR(-1) is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with snd\_dtq.

- For psnd\_dtq and ipsnd\_dtq

An error E\_TMOUT is immediately returned.

- For fsnd\_dtq, ifsnd\_dtq

Regardless of whether there is any task waiting to send, the data at the top of the data queue (the oldest data) is deleted and data is stored in the tail end of the data queue.

While one task is placed into the WAITING state by snd\_dtq or tsnd\_dtq, if vrst\_dtq is issued from another task, then the task in the WAITING state is released from that state and the service call concerned is terminated with error EV\_RST.

## 5.10.2 Receives from Data Queue (rcv\_dtq, prcv\_dtq, iprcv\_dtq, trcv\_dtq)

### □ C Language API

```
ER ercd = rcv_dtq(ID dtqid, VP_INT *p_data);
ER ercd = prcv_dtq(ID dtqid, VP_INT *p_data);
ER ercd = iprcv_dtq(ID dtqid, VP_INT *p_data);
ER ercd = trcv_dtq(ID dtqid, VP_INT *p_data, TMO tmout);
```

### □ Parameter

```
dtqid      Data queue ID
p_data     Pointer to the storage to which the received data is returned
<Only for trcv_dtq>
tmout     Timeout (millisecond)
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error (1) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID	Invalid ID number (1) dtqid <= 0, VTMAX_DTQ < dtqid
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT	Polling failure or timeout
E_CTX	Context error (invoked from an unallowed system state)

### □ Function

Receives data from the data queue indicated by dtqid and stores the received data in the area pointed to by p\_data.

If the data queue contains data, the data at the top of the queue (the oldest data) is received. When data present in the data queue is received, the data queue count is decremented by 1. In addition, if there is any task for waiting to send data, the data for the task at the top of the send queue is stored in the data queue. As a result, the task waiting to send data is released from the WAITING state.

If the data queue contains no data and there is any task waiting to send data (such a situation occurs only when the size of the data queue = 0), data for the task at the top of the data send queue is received. As a result, the task waiting to send data is released from the WAITING state.

If the data queue contains no data and there are no tasks waiting to send data either, and if the service call invoked in this situation is rcv\_dtq or trcv\_dtq, then the invoking task is tied to data arrival queue (receive queue); or, in the case of the prcv\_dtq service call, it immediately returns error E\_TMOUT. The receive queue is managed in FIFO order.



For the `trcv_dtq` service call, specify a wait time in `tmout`. If a positive value is specified for `tmout` and the specified `tmout` time elapses while the wait release condition remains unmet, `E_TMOUT` is returned as error code. If `tmout = TMO_POL(0)` is specified, the service call is processed in the same way as with `prcv_dtq`. If `tmout = TMO_FEVR(-1)` is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with `rcv_dtq`.

### 5.10.3 Refers to Data Queue Status (ref\_dtq, iref\_dtq)

#### □ C Language API

```
ER ercd = ref_dtq(ID dtqid, T_RDTQ *pk_rdtq);
ER ercd = iref_dtq(ID dtqid, T_RDTQ *pk_rdtq);
```

#### □ Parameter

```
dtqid      Data queue ID
pk_rdtq    Pointer to the storage to which the data queue state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    ID      stskid;      The task ID at the top of the task wait queue to send
    ID      rtskid;      The task ID at the top of the task wait queue to receive
    UINT    sdtqcnt;     The number of data in the data queue
} T_RDTQ;
```

#### □ Error Code

```
E_ID          Invalid ID number
              (1) dtqid <= 0, VTMAX_DTQ < dtqid
E_CTX         Context error (invoked from an unallowed system state)
              Note : The E_CTX is not detected in the following cases.
                  (1) Invocation of ref_dtq from non-task context
                  (2) Invocation of iref_dtq from task context
```

#### □ Function

Refers to the status of the data queue indicated by dtqid and returns the task ID waiting to send (stskid), the task ID waiting to receive (rtskid), and the data count stored in the data queue (sdtqcnt) to the area pointed to by pk\_rdtq.

If there are no tasks waiting to send and no tasks waiting to receive, TSK\_NONE(0) is returned as the waiting task ID.

## 5.11 Synchronization and Communication Function (Mailbox)

Table 5.14 shows specifications of the mailbox function.

Mailboxes are created by mailbox[] definition in the cfg file.

Table 5.14 Specifications of the Mailbox Function

No.	Item	Content
1	Mailbox ID	1 - VTMAX_MBX *1
2	Message priority	1 - TMAX_MPRI *2
3	Mailbox attribute	TA_TFIFO : Wait task queue is managed in FIFO order TA_TPRI : Wait task queue is managed in order of task priority TA_MFIFO : Message queue is managed in FIFO order TA_MPRI : Message queue is managed in order of message priority

- Notes:
- 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of mailboxes defined in the cfg file.
  - 2 This is the macro output to kernel\_id.h by cfg600, which indicates the value specified for system.message\_pri in the .cfg file.

Table 5.15 Service Calls for Mailbox Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	snd_mbx	[S][B]	Sends to mailbox	√		√	√	√	
2	isnd_mbx				√	√	√	√	
3	rcv_mbx	[S][B]	Receives from mailbox	√		√		√	
4	prcv_mbx	[S][B]	Receives from mailbox (Polling)	√		√	√	√	
5	iprcv_mbx					√	√	√	√
6	trcv_mbx	[S]	Receives from mailbox (with Timeout)	√		√		√	
7	ref_mbx		Refers to mailbox status	√		√	√	√	
8	iref_mbx					√	√	√	√

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings :  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.11.1 Sends to Mailbox (snd\_mbx, isnd\_mbx)

### □ C Language API

```
ER ercd = snd_mbx(ID mbxid, T_MSG *pk_msg);
ER ercd = isnd_mbx(ID mbxid, T_MSG *pk_msg);
```

### □ Parameter

```
mbxid      Mailbox ID
pk_msg     Start address of the message to be sent
```

### □ Return Value

E\_OK for normal completion or error code

### □ Packet Structure

```
<Mailbox message header>
typedef struct {
    VP      msghead;      Kernel management area
} T_MSG;
<Mailbox message header with priority>
typedef struct {
    T_MSG  msgque;       Message header
    PRI    msgpri;       Message priority
} T_MSG_PRI;
```

### □ Error Code

```
E_PAR      Parameter error
            (1)msgpri<=0, mailbox.max_pri < msgpri
E_ID       Invalid ID number
            (1)mbxid<=0, VTMAX_MBX < mbxid
E_CTX     Context error (invoked from an unallowed system state)
```

## □ Function

Sends the message indicated by `pk_msg` to the mailbox indicated by `mbxid`.

If for the target mailbox there is already any task waiting to receive a message, the transmitted message is passed to the task at the top of the waiting queue, upon which the task is dequeued.

If there are no tasks waiting to receive a message, the message is tied to a message queue. The message queue is managed according to the attributes specified when the mailbox was created.

To send a message to a mailbox with `TA_MFIFO` attribute, make sure the message created has `T_MSG` structure added at the beginning of it, as shown in Figure 5.1.

To send a message to a mailbox with `TA_MPRI` attribute, make sure the message created has `T_MSG_PRI` structure added at the beginning of it, as shown in Figure 5.2.

The `T_MSG` area must not be rewritten after a message is transmitted because the kernel uses that area. Kernel operation cannot be guaranteed if this area is rewritten before a message is received after it is transmitted.

```
typedef struct {
    T_MSG  t_msg;      /* T_MSG structure          */
    B      data[8];   /* Example of a user message data */
                                /* structure (any structure)      */
} USER_MSG;
```

Figure 5.1 Example of a Message Format (TA\_MFIFO attribute)

```
typedef struct {
    T_MSG_PRI t_msg; /* T_MSG_PRI structure      */
    B         data[8]; /* Example of a user message data */
                                /* structure (any structure)      */
} USER_MSG;
```

Figure 5.2 Example of a Message Format (TA\_MPRI attribute)

## 5.11.2 Receives from Mailbox (rcv\_mbx, prcv\_mbx, iprcv\_mbx, trcv\_mbx)

### □ C Language API

```
ER ercd = rcv_mbx(ID mbxid, T_MSG **ppk_msg);
ER ercd = prcv_mbx(ID mbxid, T_MSG **ppk_msg);
ER ercd = iprcv_mbx(ID mbxid, T_MSG **ppk_msg);
ER ercd = trcv_mbx(ID mbxid, T_MSG **ppk_msg, TMO tmout);
```

### □ Parameter

```
mbxid      Mailbox ID
ppk_msg    Pointer to the storage to which the start address of the received
           message is returned
<Only for trcv_mbx>
tmout      Timeout (millisecond)
```

### □ Return Value

E\_OK for normal completion or error code

### □ Packet Structure

```
<Mailbox message header>
typedef struct {
    VP      msghead;      Kernel management area
} T_MSG;
<Mailbox message header with priority>
typedef struct {
    T_MSG  msgque;       Message header
    PRI    msgpri;       Message priority
} T_MSG_PRI;
```

### □ Error Code

```
E_PAR      Parameter error
           (1) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID       Invalid ID number
           (1)mbxid<=0, VTMAX_MBX < mbxid
E_RLWAI    Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT    Polling failure or timeout
E_CTX      Context error (invoked from an unallowed system state)
           Note : The E_CTX is not detected in the following cases.
           (1) Invocation of prcv_mbx from non-task context
           (2) Invocation of iprcv_mbx from task context
```

### □ Function

Receives a message from the mailbox indicated by `mbxid` and returns the received message's start address to the area pointed by `ppk_msg`.

If the mailbox contains no message and the service call invoked is `rcv_mbx` or `trcv_mbx`, the invoking task is tied to a message arrival queue (receive queue); or, in the case of the `prcv_mbx` and `iprcv_mbx` service calls, it immediately returns error `E_TMOOUT`. The queue is managed according to the attributes specified when the mailbox was created.

For the `trcv_mbx` service call, specify a wait time in `tmout`. If a positive value is specified for `tmout` and the specified `tmout` time elapses while the wait release condition remains unmet, `E_TMOOUT` is returned as error code. If `tmout = TMO_POL(0)` is specified, the service call is processed in the same way as with `prcv_mbx`. If `tmout = TMO_FEVR(-1)` is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with `rcv_mbx`.

### 5.11.3 Refers to Mailbox Status (ref\_mbx, iref\_mbx)

#### □ C Language API

```
ER ercd = ref_mbx(ID mbxid, T_RMBX *pk_rmbx);
ER ercd = iref_mbx(ID mbxid, T_RMBX *pk_rmbx);
```

#### □ Parameter

```
mbxid      Mailbox ID
pk_rmbx    Pointer to the storage to which the mailbox state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
(1) T_RMBX
typedef struct {
    ID      wtskid;      The task ID at the top of the task wait queue
    T_MSG   *pk_msg;    Start address of the message to be received next
} T_RMBX;

(2) T_MSG
<Mailbox message header>
typedef struct {
    VP      msghead;    Kernel management area
} T_MSG;

<Mailbox message header with priority>
typedef struct {
    T_MSG   msgque;     Message header
    PRI     msgpri;     Message priority
} T_MSG_PRI;
```

#### □ Error Code

```
E_ID          Invalid ID number
              (1) mbxid <= 0, VTMAX_MBX < mbxid

E_CTX         Context error (invoked from an unallowed system state)
              Note : The E_CTX is not detected in the following cases.
                  (1) Invocation of ref_mbx from non-task context
                  (2) Invocation of iref_mbx from task context
```

#### □ Function

Refers to the status of the mailbox indicated by mbxid and returns the waiting task ID (wtskid) and the start address of the next message to be received (pk\_msg) to the area pointed to by pk\_rmbx.

If for the target mailbox there are no waiting tasks, TSK\_NONE(0) is returned as the waiting task ID.

If the next message to be received is nonexistent, NULL(0) is returned as the message start address.



## 5.12 Extended Synchronization and Communication Function (Mutex)

Table 5.16 shows specifications of the mutex function.

Mutexes are created by mutex[] definition in the cfg file.

Table 5.16 Specifications of the Mutex Function

No.	Item	Content
1	Mutex ID	1 - VTMAX_MTX *1
2	Mutex attribute	TA_CEILING : Priority ceiling protocol *2

- Notes:
- 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of mutexes defined in the cfg file.
  - 2 This kernel has adopted a simplified priority control rule for its TA\_CEILING attribute (priority ceiling protocol). In the simplified priority control rule, although controls to heighten task priority are exercised under all circumstances, controls to lower task priority are applied only when the task concerned has no more mutexes locked (if it had multiple mutexes locked, when all of them have been freed).

Table 5.17 Service Calls for Mutex Function

No.	Service Call *1	Description	System State *2					
			T	N	E	D	U	L
1	loc_mtx	Locks mutex	√		√		√	
2	ploc_mtx	Locks mutex (Polling)	√		√	√	√	
3	tloc_mtx	Locks mutex (with Timeout)	√		√		√	
4	unl_mtx	Unlocks mutex	√		√	√	√	
5	ref_mtx	Refers to mutex status	√		√	√	√	

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings :  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.12.1 Locks Mutex (loc\_mtx, ploc\_mtx, tloc\_mtx)

### □ C Language API

```
ER ercd = loc_mtx(ID mtxid);
ER ercd = ploc_mtx(ID mtxid);
ER ercd = tloc_mtx(ID mtxid, TMO tmout);
```

### □ Parameter

```
mtxid      Mutex ID
<Only for tloc_mtx>
tmout      Timeout (millisecond)
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error (1) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID	Invalid ID number (1)mtxid<=0, VTMAX_MTX < mtxid
E_ILUSE	Illegal use of service call (1)The mutex indicated by mtxid is already locked by the issuing task (2)Ceiling priority violation (base priority of the issuing task > ceiling priority of the target mutex)
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT	Polling failure or timeout
E_CTX	Context error (invoked from an unallowed system state)

### □ Function

Locks the mutex indicated by mtxid.

If the target mutex is not locked yet, the issuing task locks the mutex. In that case, the issuing task has its current priority raised to the ceiling priority of the mutex.

If the target mutex is already locked, the issuing task is tied to a queue, in which it is kept waiting for the mutex to become available to lock. The queue is managed in order of priority.

For the tloc\_mtx service call, specify a wait time in tmout. If a positive value is specified for tmout and the specified tmout time elapses while the wait release condition remains unmet, E\_TMOUT is returned as error code. If tmout = TMO\_POL(0) is specified, the service call is processed in the same way as with ploc\_mtx. If tmout = TMO\_FEVR(-1) is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with loc\_mtx.

## 5.12.2 Unlocks Mutex (unl\_mtx)

### ❑ C Language API

```
ER ercd = unl_mtx(ID mtxid);
```

### ❑ Parameter

mtxid      Mutex ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)mtxid<=0, VTMAX_MTX < mtxid
E_ILUSE	Illegal use of service call (The issuing task has not locked the target mutex)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Unlocks the mutex indicated by mtxid.

If there is any task waiting for the target mutex, the task at the top of the mutex queue is removed from the queue, and the task locks the mutex. At that time, the task has its current priority raised to the ceiling priority of the mutex.

If there are no tasks waiting for the mutex, the mutex is placed into an unlocked state.

This kernel has adopted a simplified priority ceiling protocol for its TA\_CEILING attribute. Therefore, it is only when the invoking task has had all of its locked mutexes freed by this service call that the task's current priority is reverted to its base priority. If the invoking task still has any other mutex locked, its current priority is not changed in this service call.

### 5.12.3 Refers to Mutex Status (ref\_mtx)

#### □ C Language API

```
ER ercd = ref_mtx(ID mtxid, T_RMTX *pk_rmtx);
```

#### □ Parameter

```
mtxid      Mutex ID
pk_rmtx    Pointer to the storage to which the mutex state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    ID      htksid;      Task ID locking the mutex
    ID      wtskid;      The task ID at the top of the task wait queue
} T_RMTX;
```

#### □ Error Code

```
E_ID          Invalid ID number
               (1)mtxid<=0, VTMAX_MTX < mtxid
E_CTX         Context error (invoked from an unallowed system state)
               Note : The E_CTX is not detected in the following cases.
               (1) Invocation of ref_mtx from non-task context
```

#### □ Function

Refers to the status of the mutex indicated by mtxid and returns the task ID that has the mutex locked (htskid) and the task ID at the top of the mutex queue (wtskid) to the area pointed to by pk\_rmtx.

If there are no tasks that have the target mutex locked, TSK\_NONE(0) is returned to htksid. If there are no tasks waiting for the target mutex, TSK\_NONE(0) is returned to wtskid.

## 5.13 Extended Synchronization and Communication Function (Message Buffer)

Table 5.18 shows specifications of the message buffer function.

Message buffers are created by mutex[] definition in the cfg file.

Table 5.18 Specifications of the Message Buffer Function

No.	Item	Content
1	Message buffer ID	1 - VTMAX_MBF *1
2	Buffer size	0 or 8 - 65532 (bytes)
3	Message size that can be transmitted	1 - 65528 (bytes)
4	Message buffer attribute	TA_TFIFO : Wait task queue for sending is managed in FIFO order

Notes: 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of message buffers defined in the cfg file.

Table 5.19 Service Calls for Message Buffer Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	snd_mbf	[R]	Sends to message buffer	√		√		√	
2	psnd_mbf	[R]	Sends to message buffer (Polling)	√		√	√	√	
3	ipsnd_mbf				√	√	√	√	
4	tsnd_mbf	[R]	Sends to message buffer (with timeout)	√		√		√	
5	rcv_mbf	[R]	Receives from message buffer	√		√		√	
6	prcv_mbf	[R]	Receives from message buffer (Polling)	√		√	√	√	
7	trcv_mbf	[R]	Receives from message buffer (with Timeout)	√		√		√	
8	ref_mbf	[R]	Refers to message buffer status	√		√	√	√	
9	iref_mbf				√	√	√	√	√

Notes: 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.

- 2 The letters representing the system status have the following meanings :
- "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

### 5.13.1 Sends to Message Buffer (snd\_mbf, psnd\_mbf, ipsnd\_mbf, tsnd\_mbf)

#### □ C Language API

```
ER ercd = snd_mbf(ID mbfid, VP msg, UINT msgsz);
ER ercd = psnd_mbf(ID mbfid, VP msg, UINT msgsz);
ER ercd = ipsnd_mbf(ID mbfid, VP msg, UINT msgsz);
ER ercd = tsnd_mbf(ID mbfid, VP msg, UINT msgsz, TMO tmout);
```

#### □ Parameter

```
mbfid      Message buffer ID
msg        Start address of the message to be sent
msgsz      Size of the message to be sent (in bytes)
<Only for tsnd_mbf>
tmout      Timeout (millisecond)
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Error Code

```
E_PAR      Parameter error
            (1) msgsz=0, msgsz > maximum message size *
            (2) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID       Invalid ID number
            (1)mbfid<=0, VTMAX_MBF < mbfid
E_RLWAI    Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT    Polling failure or timeout
E_CTX      Context error (invoked from an unallowed system state)
EV_RST     Released from WAITING state by the object reset (vrst_mbf)
```

Notes : The maximum message size is defined by message\_buffer[].max\_msgsz in the cfg file.

## □ Function

Sends the message indicated by `msg` to the message buffer indicated by `mbfid`. The transmitted size is indicated in bytes by `msgsz`.

If for the target message buffer there is any task waiting to receive, the message is not stored in the message buffer, but instead passed to the task at the top of the receive queue, upon which the task is dequeued.

If for the target message buffer there is already any task waiting to send and the service call concerned is `snd_mbf` or `tsnd_mbf`, then the task is tied to a queue (send queue) in which it is kept waiting for space in the message buffer to become available; or, in the case of the `psnd_mbf` and `ipsnd_mbf` service calls, it immediately returns error `E_TMOUT`. The send queue is arranged in FIFO order.

If there are no tasks waiting to receive or no tasks waiting to send, the message is stored in the message buffer. As a result, the size of free space in the message buffer is reduced by an amount that is calculated by the equation below.

- Reduced size = (`msgsz` rounded up to a multiple of 4) + `VTSZ_MBFTBL`

Here, `VTSZ_MBFTBL` means the size of the management table (4-bytes) which is generated in the buffer area by the kernel.

If the message buffer does not have as much space as this size (including the case where the buffer size = 0) and the service call concerned is `snd_mbf` or `tsnd_mbf`, then the invoking task is tied to a send queue; or, for `psnd_mbf` and `ipsnd_mbf`, it immediately returns error `E_TMOUT`.

For the `tsnd_mbf` service call, specify a wait time in `tmout`.

If a positive value is specified for `tmout` and the specified `tmout` time elapses while the wait condition remains unmet, `E_TMOUT` is returned as error code. If `tmout = TMO_POL(0)` is specified, the service call is processed in the same way as with `psnd_mbf`. If `tmout = TMO_FEVR(-1)` is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with `snd_mbf`.

When the task placed in the top of wait queue to send is release from the `WAITING` state by `rel_wai` or `irel_wai` service call or is terminated by `ter_tsk` service call, other waiting tasks to send might be release from the `WAITING` state.

While one task is placed into the `WAITING` state by `snd_mbf` or `tsnd_mbf`, if `vrst_mbf` is issued from another task, then the task in the `WAITING` state is released from that state and the service call concerned is terminated with error `EV_RST`.

## 5.13.2 Receives from Message Buffer (rcv\_mbf, prcv\_mbf, trcv\_mbf)

### □ C Language API

```
ER_UINT msgsz = rcv_mbf(ID mbfid, VP msg);
ER_UINT msgsz = prcv_mbf(ID mbfid, VP msg);
ER_UINT msgsz = trcv_mbf(ID mbfid, VP msg, TMO tmout);
```

### □ Parameter

```
mbfid      Message buffer ID
msg        Pointer to the storage to which the received message is stored
<Only for trcv_mbf>
tmout      Timeout (millisecond)
```

### □ Return Value

Size of the received message (number of bytes, a positive value) or error code

### □ Error Code

E_PAR	Parameter error (1) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID	Invalid ID number (1)mbfid<=0, VTMAX_MBF < mbfid
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT	Polling failure or timeout
E_CTX	Context error (invoked from an unallowed system state)

### □ Function

Receives a message from the message buffer indicated by mbfid and stores the received message in the area pointed to by msg. Also, the size of the received message is returned as return parameter.

If the message buffer contains messages, the one at the top of the message queue (the oldest message) is received. When messages present in the message buffer are received this way, the size of free space in the message buffer is increased by an amount calculated by the equation below.

- Increased size = (msgsz rounded up to a multiple of 4) + VTSZ\_MBFTBL

Here, VTSZ\_MBFTBL means the size of the management table (4-bytes) which is generated in the buffer area by the kernel.

As a result, if the message buffer now has a free space larger than the size of the message that the task at the top of the message send queue was trying to send, then the message is stored in the message buffer, upon which the task is dequeued. If the message buffer is large enough to store messages for the other tasks in the send queue, the kernel processes in the same way in the order the message send queue.



If the message buffer size = 0 and there is any task waiting to send, a message for the task at the top of the send queue is received. As a result, the task kept waiting to send a message is dequeued.

If the message buffer contains no messages and there are no tasks waiting to send a message either, and if the service call invoked is `rcv_mbf` or `trcv_mbf`, then the invoking task is tied to a queue (receive queue) in which it is kept waiting for a message to arrive; or, in the case of the `prcv_mbf` service call, it immediately returns error `E_TMOUT`. The receive queue is managed in FIFO order.

For the `trcv_mbf` service call, specify a wait time in `tmout`.

If a positive value is specified for `tmout` and the specified `tmout` time elapses while the wait release condition remains unmet, `E_TMOUT` is returned as error code. If `tmout = TMO_POL(0)` is specified, the service call is processed in the same way as with `prcv_mbf`. If `tmout = TMO_FEVR(-1)` is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with `rcv_mbf`.

### 5.13.3 Refers to Message Buffer Status (ref\_mbf, iref\_mbf)

#### □ C Language API

```
ER ercd = ref_mbf(ID mbfid, T_RMBF *pk_rmbf);
ER ercd = iref_mbf(ID mbfid, T_RMBF *pk_rmbf);
```

#### □ Parameter

```
mbfid      Message Buffer ID
pk_rmbf    Pointer to the storage to which the message buffer state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    ID      stskid;      The task ID at the top of the task wait queue to send
    ID      rtskid;      The task ID at the top of the task wait queue to receive
    UINT    smsgcnt;     The number of messages in the message buffer
    SIZE    fmbfsz;     Size of free message buffer area (in bytes)
} T_RMBF;
```

#### □ Error Code

```
E_ID      Invalid ID number
          (1)mbfid<=0, VTMAX_MBF < mbfid

E_CTX     Context error (invoked from an unallowed system state)
          Note : The E_CTX is not detected in the following cases.
          (1) Invocation of ref_mbf from non-task context
          (2) Invocation of iref_mbf from task context
```

#### □ Function

Refers to the status of the message buffer indicated by mbfid and returns the task ID waiting to send (stskid), the task ID waiting to receive (rtskid), the number of messages contained in the message buffer (smsgcnt), and the free buffer size (fmbfsz) to the area pointed to by pk\_rmbf.

If there are no tasks waiting to receive or no tasks waiting to send, TSK\_NONE(0) is returned as the waiting task ID.

## 5.14 Memory Pool management Function (Fixed-sized Memory Pool)

Table 5.20 shows specifications of the fixed-sized memory pool function.

Fixed-sized memory pools are created by `memorypool[]` definition in the `cfg` file.

Table 5.20 Specifications of the Fixed-sized Memory Pool Function

No.	Item	Content
1	Fixed-sized memory pool ID	1 - VTMAX_MPF *1
2	Maximum number of memory blocks	65535
3	Maximum size of memory block	65535 (bytes)
4	Maximum pool size (block size × number of blocks)	VTMAX_AREASIZE (bytes) *2
5	Fixed-sized memory pool attribute	TA_TFIFO : Wait task queue is managed in FIFO order TA_TPRI : Wait task queue is managed in order of task priority

- Notes: 1 This is the macro output to `kernel_id.h` by `cfg600`, which indicates the number of fixed-sized memory pools defined in the `cfg` file.
- 2 This is the macro defined in `kernel.h`. The definition is 256 M-bytes.

Table 5.21 Service Calls for Fixed-sized Memory Pool Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	<code>get_mpf</code>	[S][B]	Acquires fixed-sized memory block	√		√		√	
2	<code>pget_mpf</code>	[S][B]	Acquires fixed-sized memory block (Polling)	√		√	√	√	
3	<code>ipget_mpf</code>				√	√	√	√	
4	<code>tget_mpf</code>	[S]	Acquires fixed-sized memory block (with Timeout)	√		√		√	
5	<code>rel_mpf</code>	[S][B]	Releases fixed-sized memory block	√		√	√	√	
6	<code>irel_mpf</code>					√	√	√	√
7	<code>ref_mpf</code>		Refers to fixed-sized memory pool status	√		√	√	√	
8	<code>iref_mpf</code>					√	√	√	√

- Notes: 1 The symbol "[S]" denotes  $\mu$ ITRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ ITRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ ITRON 4.0 specification.
- 2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.14.1 Acquires fixed-sized memory block (get\_mpf, pget\_mpf, ipget\_mpf, tget\_mpf)

### □ C Language API

```
ER ercd = get_mpf(ID mpfid, VP *p_blk);
ER ercd = pget_mpf(ID mpfid, VP *p_blk);
ER ercd = ipget_mpf(ID mpfid, VP *p_blk);
ER ercd = tget_mpf(ID mpfid, VP *p_blk, TMO tmout);
```

### □ Parameter

mpfid      Fixed-sized memory pool ID

p\_blk      Pointer to the storage to which the start address of the memory block is returned

<Only for tget\_mpf>

tmout      Timeout (millisecond)

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error (1) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID	Invalid ID number (1) mpfid <= 0, VTMAX_MPF < mpfid
E_RLWAI	Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT	Polling failure or timeout
E_CTX	Context error (invoked from an unallowed system state) Note: The E_CTX is not detected in the following cases. (1) Invocation of pget_mpf from non-task context (2) Invocation of ipget_mpf from task context
EV_RST	Released from WAITING state by the object reset (vrst_mpf)

### □ Function

Acquires one memory block from the fixed-sized memory pool indicated by mpfid and returns the start address of the acquired memory block to the area pointed to by p\_blk.

If there is already any task waiting to acquire a memory block, or if there are no waiting tasks but the target fixed-sized memory pool has no free blocks in it, and the service call invoked is get\_mpf or tget\_mpf, then the invoking task is tied to a memory pool memory acquisition queue; or, in the case of the pget\_mpf and ipget\_mpf service calls, it immediately returns error E\_TMOUT. The queue is managed according to the attributes specified when the fixed-sized memory pool was created.

For the tget\_mpf service call, specify a wait time in tmout. If a positive value is specified for tmout and the specified tmout time elapses while the wait release condition remains unmet, E\_TMOUT is returned as error code. If tmout = TMO\_POL(0) is specified, the service call is processed in the same way as with pget\_mpf. If tmout = TMO\_FEVR(-1) is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with get\_mpf.

While one task is placed into the WAITING state by `get_mpf` or `tget_mpf`, if `vrst_mpf` is issued from another task, then the task in the WAITING state is released from that state and the service call concerned is terminated with error `EV_RST`.

### □ Supplement

The address boundary adjustment number for the memory blocks acquired is 1.

If memory blocks need to be acquired with a larger boundary address than that, observe the following:

- (1) Set `memorypool[].siz_block` (memory block size) in the `cfg` file to a multiple of the desired boundary adjustment number.
- (2) Specify unique section name to the pool area (`memorypool[].section` in the `cfg` file) and locate the section to the address of the desired boundary adjustment number when linked.

## 5.14.2 Releases Fixed-sized Memory Pool (rel\_mpf, irel\_mpf)

### □ C Language API

```
ER ercd = rel_mpf(ID mpfid, VP blk);
ER ercd = irel_mpf(ID mpfid, VP blk);
```

### □ Parameter

```
mpfid    Fixed-sized memory pool ID
blk      Start address of the memory block to be released
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

```
E_PAR      Parameter error
            (1)blk is the address other than the memory block, or the address
            of the memory block which has been released

E_ID       Invalid ID number
            (1)mpfid<=0, VTMAX_MPF < mpfid

E_CTX      Context error (invoked from an unallowed system state)
```

### □ Function

Releases the memory block indicated by blk to the fixed-sized memory pool indicated by mpfid.

For blk, specify the start address of the memory block acquired by the get\_mpf, pget\_mpf, ipget\_mpf, or tget\_mpf service call.

If for the target fixed-sized memory pool there is any task waiting to acquire a memory block, then the block returned by the service call concerned is assigned to the task at the top of the waiting queue, upon which the task is dequeued.

### 5.14.3 Refers to Fixed-sized Memory Pool (ref\_mpf, iref\_mpf)

#### □ C Language API

```
ER ercd = ref_mpf(ID mpfid, T_RMPF *pk_rmpf);
ER ercd = iref_mpf(ID mpfid, T_RMPF *pk_rmpf);
```

#### □ Parameter

mpfid      Fixed-sized memory pool ID  
pk\_rmpf    Pointer to the storage to which the fixed-sized memory pool state is returned

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    ID      wtskid;      The task ID at the top of the task wait queue
    UINT   fblkcnt;     The number of free memory blocks
} T_RMPF;
```

#### □ Error Code

E\_ID                    Invalid ID number  
                          (1)mpfid<=0, VTMAX\_MPF < mpfid

E\_CTX                   Context error (invoked from an unallowed system state)  
                          Note: The E\_CTX is not detected in the following cases.  
                          (1) Invocation of ref\_mpf from non-task context  
                          (2) Invocation of iref\_mpf from task context

#### □ Function

Refers to the status of the fixed-sized memory pool indicated by mpfid and returns the waiting task ID (wtskid) and the number of free blocks (fblkcnt) to the area pointed to by pk\_rmpf.

If for the target memory pool there are no waiting tasks, TSK\_NONE(0) is returned as the waiting task ID.

## 5.15 Memory Pool management Function (Variable-sized Memory Pool)

Table 5.22 shows specifications of the variable-sized memory pool function.

Variable-sized memory pools are created by `variable_memorypool[]` definition in the `cfg` file.

Table 5.22 Specifications of the Variable-sized Memory Pool Function

No.	Item	Content
1	Variable-sized memory pool ID	1 - <code>VTMAX_MPL *1</code>
2	Pool size	24 - <code>VTMAX_AREASIZE (bytes) *2</code>
3	Block size	1- <code>0xBFFFFFF4 (bytes)</code>
4	Variable-sized memory pool attribute	<code>TA_TFIFO</code> : Wait task queue is managed in FIFO order

Notes: 1 This is the macro output to `kernel_id.h` by `cfg600`, which indicates the number of variable-sized memory pools defined in the `cfg` file.

2 This is the macro defined in `kernel.h`. The definition is 256 M-bytes.

Table 5.23 Service Calls for Variable-sized Memory Pool Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	<code>get_mpl</code>		Acquires variable-sized memory block	√		√		√	
2	<code>pget_mpl</code>		Acquires variable-sized memory block (Polling)	√		√	√	√	
3	<code>ipget_mpl</code>				√	√	√	√	
4	<code>tget_mpl</code>		Acquires variable-sized memory block (with Timeout)	√		√		√	
5	<code>rel_mpl</code>		Releases variable-sized memory block	√		√	√	√	
6	<code>ref_mpl</code>		Refers to variable-sized memory pool status	√		√	√	√	
7	<code>iref_mpl</code>				√	√	√	√	

Notes: 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.

2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.



## 5.15.1 Acquires variable-sized Memory Block (get\_mpl, tget\_mpl, pget\_mpl, ipget\_mpl)

### □ C Language API

```
ER ercd = get_mpl(ID mplid, UINT blksz, VP *p_blk);
ER ercd = tget_mpl(ID mplid, UINT blksz, VP *p_blk, TMO tmout);
ER ercd = pget_mpl(ID mplid, UINT blksz, VP *p_blk);
ER ercd = ipget_mpl(ID mplid, UINT blksz, VP *p_blk);
```

### □ Parameter

```
mplid      Variable-sized memory pool ID
blksz      Memory block size (in bytes)
p_blk      Pointer to the storage to which the start address of the memory block is
           returned
<Only for tget_mpl>
tmout      Timeout (millisecond)
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

```
E_PAR      Parameter error
           (1) blksz is 0
           (2) blksz exceeds the maximum size that can be acquired.
           (3) tmout < -1, (0x7FFFFFFF - TIC_NUME)/TIC_DENO < tmout
E_ID       Invalid ID number
           (1) mplid<=0, VTMAX_MPL < mplid
E_RLWAI    Forced release from the WAITING state (accept rel_wai while waiting)
E_TMOUT    Polling failure or timeout
E_CTX      Context error (invoked from an unallowed system state)
           Note: The E_CTX is not detected in the following cases.
           (1) Invocation of pget_mpl from non-task context
           (2) Invocation of ipget_mpl from task context
EV_RST     Released from WAITING state by the object reset (vrst_mpl)
```

### □ Function

Acquires a memory block of a size (in bytes) equal to or greater than `blksz` from the variable-sized memory pool indicated by `mplid` and returns the start address of the acquired memory block to the area pointed to by `p_blk`.

If there is already any task waiting to acquire a memory block and the service call invoked is `get_mpl` or `tget_mpl`, then the invoking task is tied to a memory acquisition queue, in which it is kept waiting for memory acquisition; or, in the case of the `pget_mpl` and `ipget_mpl` service calls, it immediately returns error `E_TMOUT`. The memory acquisition queue is managed in FIFO order.

For the `tget_mpl` service call, specify a wait time in `tmout`.

If a positive value is specified for `tmout` and the specified `tmout` time elapses while the wait condition remains unmet, `E_TMOUT` is returned as error code. If `tmout = TMO_POL(0)` is specified, the service call is processed in the same way as with `pget_mpl`. If `tmout = TMO_FEVR(-1)` is specified, time-outs are not watched. Therefore, the service call is processed in the same way as with `get_mpl`.

If the task at the top of a variable-sized memory pool memory acquisition queue is removed from the queue by the `rel_wai` or `irel_wai` service call or forcibly terminated by the `ter_tsk` service call, it is possible that other tasks kept waiting to acquire variable-sized memory pool memory blocks will be released from the wait state.

While one task is placed into the WAITING state by `get_mpl` or `tget_mpl`, if `vrst_mpl` is issued from another task, then the task in the WAITING state is released from that state and the service call concerned is terminated with error `EV_RST`.

### □ Supplement

The address boundary adjustment number for the memory blocks acquired is 4.

## 5.15.2 Release Variable-sized Memory Block (rel\_mpl)

### ❑ C Language API

```
ER ercd = rel_mpl(ID mplid, VP blk);
```

### ❑ Parameter

```
mplid    Variable-sized memory pool ID
blk      Start address of the memory block to be released
```

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

```
E_PAR      Parameter error
            (1)blk is the address other than the memory block, or the address
            of the memory block which has been released

E_ID       Invalid ID number
            (1) mplid<=0, VTMAX_MPL < mplid

E_CTX     Context error (invoked from an unallowed system state)
```

### ❑ Function

Returns the memory block indicated by blk to the variable-sized memory pool indicated by mplid.

For blk, specify the start address of the memory block acquired by the get\_mpl, pget\_mpl, ipget\_mpl, or tget\_mpl service call.

When memory blocks are returned, the size of free space in a variable-sized memory pool increases. As a result, if the target variable-sized memory pool has generated in it a contiguous free space that is just as large as requested by the task at the top of the memory block acquisition queue, then the task is assigned a memory block, upon which the task is dequeued. If there are memory blocks allocatable to the other tasks in the queue, the kernel processes in the same way in the order the memory block acquisition queue.

### 5.15.3 Refers to Variable-sized Memory Pool Status (ref\_mpl, iref\_mpl)

#### □ C Language API

```
ER ercd = ref_mpl(ID mplid, T_RMPL *pk_rmpl);
ER ercd = iref_mpl(ID mplid, T_RMPL *pk_rmpl);
```

#### □ Parameter

```
mplid      Variable-sized memory pool ID
pk_rmpl    Pointer to the storage to which the variable-sized memory pool state is
           returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    ID      wtskid;      The task ID at the top of the task wait queue
    SIZE    fmplsz;     Total size of free memory blocks (in bytes)
    UINT    fblksz;     Maximum memory block size available (in bytes)
} T_RMPL;
```

#### □ Error Code

```
E_ID      Invalid ID number
           (1) mplid<=0, VTMAX_MPL < mplid
E_CTX     Context error (invoked from an unallowed system state)
           Note : The E_CTX is not detected in the following cases.
           (1) Invocation of ref_mpl from non-task context
           (2) Invocation of iref_mpl from task context
```

#### □ Function

Refers to the status of the variable-sized memory pool indicated by mplid and returns the waiting task ID (wtskid), the total size of currently free space (fmplsz), and the largest acquirable size of memory block (fblksz) to the area pointed to by pk\_rmpl.

Normally, a free space is divided up into smaller areas, so that the maximum size returned to fblksz is that of one contiguous area in a divided space. A memory block in size of up to fblksz can be acquired immediately by only invoking the pget\_mpl service call once.

## 5.16 Time Management Function (System Time)

Table 5.24 shows specifications of the system time management.

Table 5.24 Specifications of the System Time Management Function

No.	Item	Content
1	System Time	Unsigned 48 bits
2	Units of system time	1 (millisecond)
3	Update cycle of system time	TIC_NUME/TIC_DENO (millisecond) *1
4	Initial value of system time	0x000000000000
5	Maximum value of system time	0xFFFFFFFFFFFF

Notes: 1 TIC\_NUME and TIC\_DENO are the macros output to kernel\_id.h by cfg600, which respectively denote the numerator (system.tic\_nume) and the denominator (system.tic\_deno) of the time tick cycle defined in the cfg file.

Table 5.25 Service Calls for System Time Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	set_tim	[S]	Sets system time	√		√	√	√	
2	iset_tim				√	√	√	√	
3	get_tim	[S]	Refers to system time	√		√	√	√	
4	iget_tim				√	√	√	√	
5	isig_tim	[S]	Supplies time tick	(Automatically executed by specifying CMT0, CMT1, CMT2, or CMT3 for clock.timer in the cfg file)					

Notes: 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.

2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.16.1 Sets System Time (set\_tim, iset\_tim)

### □ C Language API

```
ER ercd = set_tim(SYSTIM *p_systim);
ER ercd = iset_tim(SYSTIM *p_systim);
```

### □ Parameter

p\_systim Pointer to the packet containing the system time to be set

### □ Return Value

E\_OK for normal completion or error code

### □ Packet Structure

```
typedef struct {
    UH    utime;    System time (upper)
    UW    ltime;    System time (lower)
} SYSTIM;
```

### □ Error Code

E\_CTX Context error (invoked from an unallowed system state)  
 Note: The E\_CTX is not detected in the following cases.

- (1) Invocation of set\_tim from non-task context
- (2) Invocation of iset\_tim from task context

### □ Function

Sets the current time of day that the system keeps to the value indicated by p\_systim.

Note that even if the system time is changed, the actual time of day at which the time management requests made before that (e.g., task timeouts, task delay by dly\_tsk, cyclic handlers, and alarm handlers) are generated will not change.

## 5.16.2 Refer to System Time (get\_tim, iget\_tim)

### ❑ C Language API

```
ER ercd = get_tim(SYSTIM *p_system);  
ER ercd = iget_tim(SYSTIM *p_system);
```

### ❑ Parameter

p\_system Pointer to the storage to which the system time is returned

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Packet Structure

```
typedef struct {  
    UH    utime;        System time (upper)  
    UW    ltime;        System time (lower)  
} SYSTIM;
```

### ❑ Error Code

E\_CTX Context error (invoked from an unallowed system state)  
Note: The E\_CTX is not detected in the following cases.  
(1) Invocation of get\_tim from non-task context  
(2) Invocation of iget\_tim from task context

### ❑ Function

Reads out the current value of the system time and returns the result to the area pointed to by p\_system.

### 5.16.3 Supplies Time Tick (isig\_tim)

#### □ Function

Updates the system time.

If either CMT0, CMT1, CMT2 or CMT3 is specified for clock.timer in the cfg file, the system is configured in such a way that processing equivalent of the isig\_tim service call is automatically executed in cycles calculated by TIC\_NUME / TIC\_DENO (millisecond). In other words, this function is not a service call and, therefore, does not need to be invoked from the application.

When a time tick is supplied, the kernel performs the following time-related processing:

- (1) Updates the system time
- (2) Activates time event handler
- (3) Performs time-out processing on tasks placed in the WAITING state by tslp\_tsk or other service call with time-outs included



## 5.17 Time Management Function (Cyclic Handler)

Table 5.26 shows specifications of the cyclic handler function.

Cyclic handlers are created by `cyclic_hand[]` definition in the `cfg` file.

Table 5.26 Specifications of the Cyclic Handler Function

No.	Item	Content
1	Cyclic handler ID	1 - VTMAX_CYC *1
2	Activation cycle	1 - (0x7FFFFFFF - TIC_NUME)/TIC_DENO *2
3	Activation phase	0 - (0x7FFFFFFF - TIC_NUME)/TIC_DENO *2
4	Extension information (parameters passed to handler)	32 bits
5	Cyclic handler attribute	TA_HLNG : Written in high-level language *3 TA_ASM : Written in assembly language *3 TA_STA : Cyclic handler is an operational state after creation TA_PHS : Cyclic handler is activated preserving the activation phase

- Notes:
- 1 This is the macro output to `kernel_id.h` by `cfg600`, which indicates the number of cyclic handlers defined in the `cfg` file.
  - 2 TIC\_NUME and TIC\_DENO are the macros output to `kernel_id.h` by `cfg600`, which respectively denote the numerator (`system.tic_num`) and the denominator (`system.tic_deno`) of the time tick cycle defined in the `cfg` file.
  - 3 In the current implementation, there are no differences in cyclic handler operation due to these attributes.

Table 5.27 Service Calls for Cyclic Handler Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	<code>sta_cyc</code>	[S][B]	Starts cyclic handler operation	√		√	√	√	
2	<code>ista_cyc</code>				√	√	√	√	
3	<code>stp_cyc</code>	[S][B]	Stops cyclic handler operation	√		√	√	√	
4	<code>istp_cyc</code>				√	√	√	√	
5	<code>ref_cyc</code>		Refers to cyclic handler status	√		√	√	√	
6	<code>iref_cyc</code>				√	√	√	√	

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings:  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.17.1 Starts Cyclic Handler Operation (sta\_cyc, ista\_cyc)

### □ C Language API

```
ER ercd = sta_cyc(ID cycid);
ER ercd = ista_cyc(ID cycid);
```

### □ Parameter

cycid      Cyclic handler ID

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_ID	Invalid ID number (1)cycid<=0, VTMAX_CYC < cycid
E_CTX	Context error (invoked from an unallowed system state) Note: The E_CTX is not detected in the following cases. (1) Invocation of sta_cyc from non-task context (2) Invocation of iref_cyc from task context

### □ Function

Places the cyclic handler indicated by cycid into an operating state.

Unless TA\_PHS is specified for the cyclic handler attribute, the handler is activated each time the activation cycle elapses beginning from the time of day at which this service call was invoked.

If a cyclic handler currently in an operating state and that has had TA\_PHS unspecified is specified, the service call only resets the time of day at which the cyclic handler will be activated next.

If TA\_PHS is specified, the cyclic handler is activated cyclically beginning from the time of day at which it was created, so that the service call does not set the activation time.

## 5.17.2 Stops Cyclic Handler Operation (stp\_cyc, istp\_cyc)

### ❑ C Language API

```
ER ercd = stp_cyc(ID cycid);  
ER ercd = istp_cyc(ID cycid);
```

### ❑ Parameter

cycid      Cyclic handler ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)cycid<=0, VTMAX_CYC < cycid
E_CTX	Context error (invoked from an unallowed system state) Note: The E_CTX is not detected in the following cases. (1) Invocation of stp_cyc from non-task context (2) Invocation of istp_cyc from task context

### ❑ Function

Places the cyclic handler indicated by cycid into an inactive state.

### 5.17.3 Refers to Cyclic Handler Status (ref\_cyc, iref\_cyc)

#### □ C Language API

```
ER ercd = ref_cyc(ID cycid, T_RCYC *pk_rcyc);
ER ercd = iref_cyc(ID cycid, T_RCYC *pk_rcyc);
```

#### □ Parameter

```
cycid      Cyclic handler ID
pk_rcyc    Pointer to the storage to which the cyclic handler state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    STAT   cycstat;      Cyclic handler operation state
    RELTIM lefttim;     Time left before the next activation
} T_RCYC;
```

#### □ Error Code

```
E_ID          Invalid ID number
              (1)cycid<=0, VTMAX_CYC < cycid
E_CTX         Context error (invoked from an unallowed system state)
              Note: The E_CTX is not detected in the following cases.
              (1) Invocation of ref_cyc from non-task context
              (2) Invocation of iref_cyc from task context
```

#### □ Function

Refers to the status of the cyclic handler indicated by cycid and returns its operating state (cycstat) and the remaining time before the handler is activated (lefttim) to the area pointed to by pk\_rcyc.

The value returned to cycstat represents the operating state of the target cyclic handler.

- TCYC\_STP (0x00000000) : Cyclic handler not operating
- TCYC\_STA (0x00000001) : Cyclic handler operating

The value returned to lefttim represents a remaining time relative to the time of day at which the target cyclic handler will be activated next. If the handler will activate at the next time-tick, 0 is returned.

If the target cyclic handler is not operating, the value of lefttim is indeterminate.

## 5.18 Time Management Function (Alarm Handler)

Table 5.28 shows specifications of the alarm handler function.

Alarm handlers are created by alarm\_hand[] definition in the cfg file.

Table 5.28 Specifications of the Alarm Handler Function

No.	Item	Content
1	Alarm handler ID	1 - VTMAX_ALM *1
2	Activation time	0 - (0x7FFFFFFF - TIC_NUME)/TIC_DENO *2
3	Extension information (parameters passed to handler)	32 bits
4	Alarm handler attribute	TA_HLNG : Written in high-level language *3 TA_ASM : Written in assembly language *3

- Notes:
- 1 This is the macro output to kernel\_id.h by cfg600, which indicates the number of alarm handlers defined in the cfg file.
  - 2 TIC\_NUME and TIC\_DENO are the macros output to kernel\_id.h by cfg600, which respectively denote the numerator (system.tic\_nume) and the denominator (system.tic\_deno) of the time tick cycle defined in the cfg file.
  - 3 In the current implementation, there are no differences in alarm handler operation due to these attributes.

Table 5.29 Service Calls for Alarm Handler Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	sta_alm		Starts alarm handler operation	√		√	√	√	
2	ista_alm				√	√	√	√	
3	stp_alm		Stops alarm handler operation	√		√	√	√	
4	istp_alm				√	√	√	√	
5	ref_alm		Refers to alarm handler status	√		√	√	√	
6	iref_alm				√	√	√	√	

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings:  
"T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.18.1 Starts Alarm Handler Operation (sta\_alm, ista\_alm)

### □ C Language API

```
ER ercd = sta_alm(ID almid, RELTIM almtim);
ER ercd = ista_alm(ID almid, RELTIM almtim);
```

### □ Parameter

```
almid      Alarm handler ID
almtim     Activation time
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

```
E_PAR      Parameter error
            (1) (0x7FFFFFFF - TIC_NUME)/TIC_DENO < almtim

E_ID       Invalid ID number
            (1) almid <= 0, VTMAX_ALM < almid

E_CTX     Context error (invoked from an unallowed system state)
            Note: The E_CTX is not detected in the following cases.
            (1) Invocation of sta_alm from non-task context
            (2) Invocation of ista_alm from task context
```

### □ Function

Sets the activation time of the alarm handler indicated by almid so that the handler will start operating a relative time (specified by almtim) after the time of day at which the service call was invoked.

If an alarm handler already operating is specified, the service call clears the previously set activation time and sets a new activation time.

If the value 0 is specified for almtim, the alarm handler is activated at the next time tick.

## 5.18.2 Stops Alarm Handler (stp\_alm, istp\_alm)

### □ C Language API

```
ER ercd = stp_alm(ID almid);  
ER ercd = istp_alm(ID almid);
```

### □ Parameter

almid      Alarm handler ID

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_ID	Invalid ID number (1) almid ≤ 0, VTMAX_ALM < almid
E_CTX	Context error (invoked from an unallowed system state) Note: The E_CTX is not detected in the following cases. (1) Invocation of stp_alm from non-task context (2) Invocation of istp_alm from task context

### □ Function

Clears the activation time that is set for the alarm handler indicated by almid, thereby causing the handler to stop operating.

### 5.18.3 Refers to Alarm Handler Status (ref\_alm, iref\_alm)

#### □ C Language API

```
ER ercd = ref_alm(ID almid, T_RALM *pk_ralm);
ER ercd = iref_alm(ID almid, T_RALM *pk_ralm);
```

#### □ Parameter

```
almid      Alarm handler ID
pk_ralm    Pointer to the storage to which the alarm handler state is returned
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Packet Structure

```
typedef struct {
    STAT   almstat;    Alarm handler operation state
    RELTIM lefttim;    Time left before the activation
} T_RALM;
```

#### □ Error Code

```
E_ID          Invalid ID number
              (1) almid <= 0, VTMAX_ALM < almid
E_CTX         Context error (invoked from an unallowed system state)
              Note: The E_CTX is not detected in the following cases.
              (1) Invocation of ref_alm from non-task context
              (2) Invocation of iref_alm from task context
```

#### □ Function

Refers to the status of the alarm handler indicated by almid and returns its operating state (almstat) and the remaining time before the handler is activated (lefttim) to the area pointed to by pk\_ralm.

The value returned to almstat represents the operating state of the target alarm handler.

- TALM\_STP (0x00000000) : Alarm handler not operating
- TALM\_STA (0x00000001) : Alarm handler operating

The value returned to lefttim represents a relative remaining time before the target alarm handler will be activated. If the handler will activate at the next time-tick, 0 is returned.

If the target alarm handler is not operating, the value of lefttim is indeterminate.



## 5.19 System State Management Function

Table 5.30 Service Calls for System State Management Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	rot_rdq	[S][B]	Rotates task precedence	√		√	√	√	
2	irotd_rdq	[S][B]			√	√	√	√	
3	get_tid	[S][B]	Refers to task ID in the RUNNING state	√		√	√	√	
4	iget_tid	[S]			√	√	√	√	
5	loc_cpu	[S][B]	Locks the CPU	√		√	√	√	√
6	iloc_cpu	[S]			√	√	√	√	√
7	unl_cpu	[S][B]	Unlocks the CPU	√		√	√	√	√
8	iunl_cpu	[S]			√	√	√	√	√
9	dis_dsp	[S][B]	Disable dispatching	√		√	√	√	
10	ena_dsp	[S][B]	Enable dispatching	√		√	√	√	
11	sns_ctx	[S]	Refers to contest state	√	√	√	√	√	√
12	sns_loc	[S]	Refers to CPU-locked state	√	√	√	√	√	√
13	sns_dsp	[S]	Refers to dispatching-disabled state	√	√	√	√	√	√
14	sns_dpn	[S]	Refers to dispatching-pending state	√	√	√	√	√	√
15	vsta_knl	[V]	Starts kernel	√	√	√	√	√	√
16	ivsta_knl	[V]			√	√	√	√	√
17	vsys_dwn	[V]	Terminates system	√	√	√	√	√	√
18	ivsys_dwn	[V]			√	√	√	√	√

- Notes: 1 The symbol "[S]" denotes  $\mu$ ITRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ ITRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ ITRON 4.0 specification.
- 2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.19.1 Rotates Task Precedence (rot\_rdq, irot\_rdq)

### ❑ C Language API

```
ER ercd = rot_rdq(PRI tskpri);
ER ercd = irot_rdq(PRI tskpri);
```

### ❑ Parameter

tskpri      Task priority

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_PAR	Parameter error
	(1) tskpri < 0, TMAX_MPRI < tskpri
	(2) In an invocations from non-task context, tskid = TSK_SELF (0)
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Rotates the ready queue with its priority indicated by tskpri by removing the task tied at the top of the queue and then tying it anew to the tail end of the queue.

If tskpri = TPRI\_SELF(0) is specified for rot\_rdq, the ready queue that has the issuing task's base priority is rotated.

Note that although the base priority of a task is the same as its current priority unless the mutex function is used, if the task has a mutex being locked to it, its base priority and current priority generally do not match.

Therefore, while a mutex is locked, even if TPRI\_SELF is specified for rot\_rdq, it is impossible to rotate the ready queue whose priority matches that of the issuing task.

## 5.19.2 Refers to Task ID in the RUNNING State (get\_tid, iget\_tid)

### ❑ C Language API

```
ER ercd = get_tid(ID *p_tskid);  
ER ercd = iget_tid(ID *p_tskid);
```

### ❑ Parameter

p\_tskid    Pointer to the storage to which the task ID is returned

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E\_CTX                    Context error (invoked from an unallowed system state)

Note: The E\_CTX is not detected in the following cases.

- (1) Invocation of get\_tid from non-task context
- (2) Invocation of iget\_tid from task context

### ❑ Function

Returns the task ID currently in the RUNNING state to the area pointed to by p\_tskid.

Specifically, if the service call is invoked from a task context, the ID of the issuing task is returned; if invoked from a non-task context, the ID of the task that was being executed then is returned. If tasks in an execution state are nonexistent, TSK\_NONE(0) is returned.

### 5.19.3 Locks the CPU (loc\_cpu, iloc\_cpu)

#### □ C Language API

```
ER ercd = loc_cpu(void);
ER ercd = iloc_cpu(void);
```

#### □ Return Value

E\_OK for normal completion or error code

#### □ Error Code

E_CTX	Context error (invoked from an unallowed system state) Note: The E_CTX is not detected in the following cases. (1) Invocation of loc_cpu from non-task context (2) Invocation of iloc_cpu from task context
E_ILUSE	Illegal use of service call (loc_cpu is called while the interrupt mask has been changed to other than 0 by using chg_ims)

#### □ Function

Places the system status into the CPU-locked state.

Characteristics of the CPU-locked state are outlined below.

- (1) While in the CPU-locked state, task scheduling is not performed. (refer to supplement)
- (2) The interrupts whose priority levels are lower than or equal to system.system\_IPL (kernel interrupt mask level) specified in the cfg file are masked. (The IPL bits of the PSW register are changed to system.system\_IPL.)
- (3) Only the following service calls are invocable from the CPU-locked state:
  - ext\_tsk
  - loc\_cpu, iloc\_cpu
  - unl\_cpu, iunl\_cpu
  - sns\_ctx
  - sns\_loc
  - sns\_dsp
  - sns\_dpn
  - vsys\_dwn, ivsys\_dwn

The system is freed from the CPU-locked state by one of the following operations:

- (a) Invocation of the unl\_cpu or iunl\_cpu service call
- (b) Invocation of the ext\_tsk service call (including return from a task entry function)

Transition between the CPU-locked state and the CPU-unlocked state occurs only when the loc\_cpu, iloc\_cpu, unl\_cpu, iunl\_cpu, or ext\_tsk service call is executed. It is necessary that when any kernel-interrupt handler or time event handler is finished, the system must be in the CPU-unlocked state. If not, the system will go down at ret\_int service call. Note that when any of these handlers starts, the system is always in the CPU-unlocked state.

When the `loc_cpu` is called while the interrupt mask has been changed to other than 0 by using `chg_ims`, `loc_cpu` returns `E_ILUSE` error.

Even if this service call is invoked again while the system is already in the CPU-locked state, no errors are assumed, but the request is not queued.

#### **□ Supplement**

The CPU-locked state and the dispatching-disabled state are managed independently of each other.

## 5.19.4 Unlocks the CPU (unl\_cpu, iunl\_cpu)

### □ C Language API

```
ER ercd = unl_cpu(void);  
ER ercd = iunl_cpu(void);
```

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E\_CTX                      Context error (invoked from an unallowed system state)

### □ Function

Frees the system from the CPU-locked state.

Concretely, the unl\_cpu enables task-dispatching, and changes the interrupt mask (PSW.IPL) to 0. However, the dispatching-disabled state continues after calling the unl\_cpu when the loc\_cpu has been called in the dispatching-disabled state by the dis\_dsp. (refer to supplement)

The iunl\_cpu returns the interrupt mask to just before iunl\_cpu.

It is necessary to release CPU-locked state before the handler ends when iloc\_cpu is used by the handler.

Even if this service call is invoked from the CPU-unlocked state, no errors are assumed, but the request is not queued.

### □ Supplement

The CPU-locked state and the dispatching-disabled state are managed independently of each other. Therefore, in the unl\_cpu and iunl\_cpu service calls, the dispatching-disabled state entered into by an invocation of the dis\_dsp service call cannot be canceled.

### 5.19.5 Disables Dispatching (dis\_dsp)

#### ❑ C Language API

```
ER ercd = dis_dsp(void);
```

#### ❑ Return Value

E\_OK for normal completion or error code

#### ❑ Error Code

E\_CTX Context error (invoked from an unallowed system state)

#### ❑ Function

Places the system status into the dispatching-disabled state.

Characteristics of the dispatching-disabled state are outlined below;

- (1) Since task scheduling is no longer performed, in no case will tasks except the issuing task be transitioned to the RUNNUNG state.
- (2) Interrupts are accepted.
- (3) No service calls can be invoked that will result in tasks being placed into the WAITING state.

The system is freed from the dispatching-disabled state by one of the following operations:

- (1) Invocation of the ena\_dsp service call
- (2) Invocation of the ext\_tsk service call (including return from a task entry function)
- (3) Changes the interrupt mask (PSW.IPL) to 0 by using the chg\_ims service call

Transition between the dispatching-disabled state and the dispatching-enabled state occurs only when the dis\_dsp, ena\_dsp, or ext\_tsk service call is executed.

Be aware that while the system is placed in the dispatching-disabled state by this service call, even if the status of the issuing task is inspected by the ref\_tsk, iref\_tsk, ref\_tst, or iref\_tst service call, the task status may not appear to be in an execution state.

Even if this service call is invoked again while the system is already in the dispatching-disabled state, no errors are assumed, but the request is not queued.

### 5.19.6 Enables Dispatching (ena\_dsp)

#### ❑ C Language API

```
ER ercd = ena_dsp(void);
```

#### ❑ Return Value

E\_OK for normal completion or error code

#### ❑ Error Code

E\_CTX                      Context error (invoked from an unallowed system state)

#### ❑ Function

Frees the system from the dispatching-disabled state that was set by the dis\_dsp or chg\_ims service call and performs scheduling of tasks.

Even if this service call is invoked from the dispatching-enabled state, no errors are assumed, but the request is not queued.



### 5.19.7 Refers to Context State (sns\_ctx)

#### ❑ C Language API

```
BOOL state = sns_ctx(void);
```

#### ❑ Return Value

```
TRUE      Non-task context  
FALSE     Task Context
```

Note, when the context error occurs, error E\_CTX is returned.

#### ❑ Error Code

```
E_CTX      Context error (invoked from an unallowed system state)
```

#### ❑ Function

Examines the type of current context.

This service call can also be invoked from the CPU-locked state.

### 5.19.8 Refers to CPU-Locked State (sns\_loc)

#### ❑ C Language API

```
BOOL state = sns_loc(void);
```

#### ❑ Return Value

```
TRUE      CPU-locked state  
FALSE     CPU-unlocked state
```

Note, when the context error occurs, error E\_CTX is returned.

#### ❑ Error Code

```
E_CTX      Context error (invoked from an unallowed system state)
```

#### ❑ Function

Checks to see if the system is in the CPU-locked state.

This service call can also be invoked from the CPU-locked state.

### 5.19.9 Refers to Dispatching-Disabled Dstate (sns\_dsp)

#### ❑ C Language API

```
BOOL state = sns_dsp(void);
```

#### ❑ Return Value

TRUE            Dispatching-disabled state

FALSE          Dispatching-enabled state

Note, when the context error occurs, error E\_CTX is returned.

#### ❑ Error Code

E\_CTX                      Context error (invoked from an unallowed system state)

#### ❑ Function

Checks to see if the system is in the dispatching-disabled state.

This service call can also be invoked from the CPU-locked state.

### 5.19.10 Refers to Dispatching-Pending State (sns\_dpn)

#### ❑ C Language API

```
BOOL state = sns_dpn(void);
```

#### ❑ Return Value

TRUE            Dispatching-pending state

FALSE          Not in dispatching-pending state

Note, when the context error occurs, error E\_CTX is returned.

#### ❑ Error Code

E\_CTX                    Context error (invoked from an unallowed system state)

#### ❑ Function

Checks to see if dispatching is put on hold.

When one of the following conditions is met, dispatching is assumed to be put on hold:

- (1) The system is in the dispatching-disabled state.
- (2) The system is in the CPU-locked state.
- (3) The application is being executed in the non-task context.

This service call can also be invoked from the CPU-locked state.

### 5.19.11 Starts Kernel (vsta\_knl, ivsta\_knl)

#### □ C Language API

```
void vsta_knl(void);  
void ivsta_knl(void);
```

#### □ Function

Activates the kernel. In no case does the application return from this service call.

The following outlines processing performed by these service calls.

- (1) Initializes INTB register to the start address of the relocatable interrupt vector table generated by cfg600.
- (2) Initializes kernel internal tables.
- (3) Creates objects defined by cfg file.
- (4) Enters the multitasking environment

These service calls must be called in the following states.

- (1) The CPU must not accept any interrupt. (ex. PSW.I=0)
- (2) Supervisor mode (PSW.PM=0)

Note that E\_CTX errors are not detected in this service call.

This service call can be called when the interrupt mask level (PSW.IPL) is higher than the kernel interrupt mask level (system.system\_IPL)

This service call is the function outside the range of  $\mu$ ITRON 4.0 specifications

## 5.19.12 Terminates System (vsys\_dwn, ivsys\_dwn)

### □ C Language API

```
void vsys_dwn(W type, VW inf1, VW inf2, VW inf3);  
void ivsys_dwn(W type, VW inf1, VW inf2, VW inf3);
```

### □ Parameter

type	Error type
inf1	System abnormal information 1
inf2	System abnormal information 2
inf3	System abnormal information 3

### □ Function

Passes control to the system-down routine.

For type, specify a value (1 - 0x7FFFFFFF) that represents the type of error that occurs. Note that the values equal to or less than 0 are reserved for use by the system.

The system-down routine is also invoked when an abnormal condition in the kernel is detected.

This service call can be invoked from any state.

In no case will the application return from this service call.

Furthermore, E\_CTX errors are not detected in this service call.

For details about parameter specifications, see Section 6.6, "System-Down Routine."

This service call can be called when the interrupt mask level (PSW.IPL) is higher than the kernel interrupt mask level (system.system\_IPL)

This service call is the function outside the range of  $\mu$ ITRON 4.0 specifications.

## 5.20 Interrupt management Function

Table 5.31 Service Calls for Interrupt Management Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	chg_ims		Changes interrupt mask	√		√	√	√	√
2	ichg_ims				√	√	√	√	
3	get_ims		Refers to interrupt mask	√		√	√	√	√
4	iget_ims				√	√	√	√	
5	ret_int	[S][B]	Returns from kernel interrupt handler		√	√	√	√	

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ TRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ TRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ TRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.20.1 Changes Interrupt Mask (chg\_ims, ichg\_ims)

### □ C Language API

```
ER ercd = chg_ims(IMASK imask);
ER ercd = ichg_ims(IMASK imask);
```

### □ Parameter

imask          Interrupt mask

### □ Return Value

E\_OK for normal completion or error code

### □ Error Code

E_PAR	Parameter error
	(1) Any value other than 0-15 specified for imask
E_CTX	Context error (invoked from an unallowed system state)

### □ Function

Changes the CPU's interrupt mask (PSW.IPL) to the value specified by imask.

For imask, any value in the range 0–15 can be specified.

In the chg\_ims service call, the system state shifts to the dispatching-disabled state when specified imask is other than 0 (this is equivalent to the dis\_dsp service call.) And the system state shifts to the dispatching-enabled state when specified imask is 0 (this is equivalent to the ena\_dsp service call.) On the other hand, the ichg\_ims service call doesn't cause the transition of the dispatching-disabled state and the dispatching-enabled state.

Note, the PSW register is handled as the task context register. (refer to Supplement #2)

This service call can be called when the interrupt mask level (PSW.IPL) is higher than the kernel interrupt mask level (system.system\_IPL).

It is necessary to return it based on the interrupt mask before task or handler is ended.

### □ Supplement

1. In the non-task context, the interrupt mask must not be lowered more than the value at the initiation.
2. The system state shifts to the dispatching-enabled state at that time if the ena\_dsp is called after the interrupt mask (PSW.IPL) is changed other than 0.  
The interrupt mask is changed in the state of the task of the dispatch destination when dispatching it to another task because the PSW is handled as the task context register.
3. The loc\_cpu returns E\_ILUSE error while having changed the interruption mask excluding 0.



4. When the interrupt mask is higher than the kernel interrupt mask level (system.system\_IPL), service calls that can use it is limited as follows.  
    chg\_ims, ichg\_ims, get\_ims, iget\_ims, vsta\_knl, ivsta\_knl, vsys\_dwn, ivsys\_dwn

## 5.20.2 Refers to Interrupt Mask (get\_ims, iget\_ims)

### ❑ C Language API

```
ER ercd = get_ims(IMASK *p_ims);  
ER ercd = iget_ims(IMASK *p_ims);
```

### ❑ Parameter

p\_ims Pointer to storage to which the interrupt mask level is returned

### ❑ Return Value

E\_OK for normal completion

### ❑ Function

Returns the current interrupt mask level (PSW.IPL) to the area pointed to by p\_ims.

Note that E\_CTX errors are not detected in this service call.

This service call can be called when the interrupt mask level (PSW.IPL) is higher than the kernel interrupt mask level (system.system\_IPL)

### 5.20.3 Returns from kernel interrupt handler (ret\_int)

#### □ C Language API

None (This service call is invoked automatically at termination of an interrupt handler according to its definition in the cfg file.)

Service calls ret\_int does not return to the position where it was issued.

When the following error is detected, the system will go down.

E\_CTX                      Context error (invoked from an unallowed system state)

#### □ Function

Performs processing for return from a kernel interrupt handler.

When returning from a kernel interrupt handler which occurred while executing in task-context, the scheduler is put to work and tasks are switched depending on the result.

Other case, returns to the interrupted program.

The interrupt mask level (PSW.IPL) at the time a kernel interrupt handler is finished, i.e., when this service call is invoked must be less than or equal to the kernel interrupt mask (system.system\_IPL). Otherwise, a context error is detected in this service call and system-down results. The following cases apply to this:

- (1) Cases where a non-kernel interrupt handler is erroneously defined as a kernel interrupt handler
- (2) Cases where PSW.IPL is changed to less than the kernel mask level (system.system\_IPL) in a kernel interrupt handler and the changed mask level is left intact when the handler is finished

In addition, when this service call is issued in the CPU-locked state or from task-context, a system-down results.

#### □ Supplement

There are two types of interrupts: one kernel interrupt and one non-kernel interrupt. For details, see Section 3.7.1, "Type of Interrupt."

To define a kernel interrupt handler, specify YES for interrupt\_vector[].os\_int in the cfg file. In this case, when the relevant handler function is compiled, an object code is generated that invokes this service call at the end of the handler.

On the other hand, the non-kernel interrupt handler is defined differently depending on whether it is a relocatable vector or a fixed vector interrupt. To define the former, specify NO for interrupt\_vector[].os\_int in the cfg file; to define the latter, use interrupt\_fvector[]. In these cases, when the relevant handler function is compiled, an object code is generated that causes the handler to be returned to the main at the end of it by an RTE instruction.

## 5.21 System Configuration Management Function

Table 5.32 Service Calls for System Configuration Management Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	ref_ver	[S]	Refers to version information	√		√	√	√	
2	iref_ver				√	√	√	√	

- Notes:
- 1 The symbol "[S]" denotes  $\mu$ ITRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ ITRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ ITRON 4.0 specification.
  - 2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.21.1 Refers to Version Information (ref\_ver, iref\_ver)

### □ C Language API

```
ER ercd = ref_ver(T_RVER *pk_rver);
ER ercd = iref_ver(T_RVER *pk_rver);
```

### □ Parameter

pk\_rver Pointer to storage to which the version formation is returned

### □ Return Value

E\_OK for normal completion

### □ Error Code

E\_CTX Context error (invoked from an unallowed system state)  
 Note: The E\_CTX is not detected in the following cases.  
 (1) Invocation of ref\_ver from non-task context  
 (2) Invocation of iref\_ver from task context

### □ Packet Structure

```
typedef struct {
    UH    maker;      Kernel maker code
    UH    prid;       Identification number of the kernel
    UH    spver;      Version number of the ITRON specification
    UH    prver;      Version number of the kernel
    UH    prno[4];    management information of the kernel
} T_RVER;
```

## □ Function

Reads out information about the kernel version currently being executed and returns the result to the area pointed to by `pk_rver`.

The packet pointed to by `pk_rver` will have the following information returned to it:

### (1) `maker`

Represents the manufacturer who created the kernel. For the kernel described herein, `maker = 0x0115` which means Renesas Technology Corp.

### (2) `prid`

Represents the number that identifies the kernel and the type of VLSI. For the kernel described herein, `0x0015` is returned.

### (3) `spver`

Represents the specification to which the kernel conforms. This information consists of separate bit fields, each having the following meaning:

- Bits15 - 12 : MAGIC (number to identify a series in TRON specifications)  
For the kernel described herein, this is `0x5` ( $\mu$ TRON specification)
- Bits 11 - 0 : SpecVer (version number of TRON specification on which product is based)  
For the kernel described herein, this is `0x403` ( $\mu$ TRON 4.0 specification Ver.4.03)

### (4) `prver`

Represents the version number of the kernel.

The value of `prver` differs with each product version. See the release notes included with your product. For example, `prver` for V.1.00 Release 00 is `0x0100`.

### (5) `prno`

Represents product management information and product number, etc.

The value from `prno[0]` to `prno[3]` for the kernel described herein is `0x0000`.

## 5.22 Object Reset Function

The object reset function is the function to revert various objects to their initial state. This function is outside  $\mu$ ITRON 4.0 specification.

Table 5.33 Service Calls for Object Reset Function

No.	Service Call *1		Description	System State *2					
				T	N	E	D	U	L
1	vrst_dtq	[V]	Resets data queue	√		√	√	√	
2	vrst_mbx	[V]	Resets mailbox	√		√	√	√	
3	vrst_mbf	[V]	Resets message buffer	√		√	√	√	
4	vrst_mpf	[V]	Resets fixed-sized memory pool	√		√	√	√	
5	vrst_mpl	[V]	Resets variable-sized memory pool	√		√	√	√	

- Notes: 1 The symbol "[S]" denotes  $\mu$ ITRON 4.0-compliant, standard-profile service calls; "[B]" denotes  $\mu$ ITRON 4.0-compliant, basic-profile service calls; and "[V]" denotes service calls other than  $\mu$ ITRON 4.0 specification.
- 2 The letters representing the system status have the following meanings:  
 "T" invocable from task contexts, "N" invocable from non-task contexts, "E" invocable from a dispatching-enabled state, "D" invocable from a dispatching-disabled state, "U" invocable from the CPU-unlocked state, "L" invocable from the CPU-locked state.

## 5.22.1 Resets Data Queue (vrst\_dtq)

### ❑ C Language API

```
ER ercd = vrst_dtq( ID dtqid );
```

### ❑ Parameter

dtqid      Data queue ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)dtqid<=0, VTMAX_DTQ < dtqid
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Resets the data queue indicated by dtqid.

More specifically, this service call clears the data stored in the data queue and, if there is any task waiting to send to the data queue, frees those tasks from the WAITING state. In this case, the task freed from the WAITING state will have error code EV\_RST returned to it.

Note that tasks waiting to receive from the data queue are not freed from the WAITING state.

This service call is the function outside  $\mu$ ITRON 4.0 specification.



## 5.22.2 Resets Mailbox(vrst\_mbx)

### ❑ C Language API

```
ER ercd = vrst_mbx( ID mbxid );
```

### ❑ Parameter

mbxid      Mailbox ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)mbxid<=0, VTMAX_MBX < mbxid
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Resets the mailbox indicated by mbxid.

More specifically, this service call empties the message queue.

This service call is the function outside  $\mu$ ITRON 4.0 specification.

## 5.22.3 Resets Message Buffer (vrst\_mbf)

### ❑ C Language API

```
ER ercd = vrst_mbf( ID mbfid );
```

### ❑ Parameter

mbfid      Message buffer ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)mbfid<=0, VTMAX_MBF < mbfid
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Resets the message buffer indicated by mbfid.

More specifically, this service call clears the messages stored in the message buffer and, if there is any task waiting to send to the message buffer, frees those tasks from the WAITING state. In this case, the task freed from the WAITING state will have error code EV\_RST returned to it.

Note that tasks waiting to receive from the message buffer are not freed from the WAITING state.

This service call is the function outside  $\mu$ ITRON 4.0 specification.

## 5.22.4 Resets Fixed-sized Memory Pool (vrst\_mpf)

### ❑ C Language API

```
ER ercd = vrst_mpf( ID mpfid );
```

### ❑ Parameter

mpfid      Fixed-sized memory pool ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)mpfid<=0, VTMAX_MPF < mpfid
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Resets the fixed-sized memory pool indicated by mpfid.

More specifically, this service call changes the status of all memory blocks to an unused state and, if there is any task waiting to get a memory block, frees those tasks from the WAITING state. In this case, the task freed from the WAITING state will have error code EV\_RST returned to it.

Since all memory blocks are handled as 'unused' state, once this service call is executed, the memory blocks previously acquired, if any, cannot be used.

This service call is the function outside  $\mu$ ITRON 4.0 specification.

## 5.22.5 Resets Variable-sized Memory Pool (vrst\_mpl)

### ❑ C Language API

```
ER ercd = vrst_mpl( ID mplid );
```

### ❑ Parameter

mplid            Variable-sized memory pool ID

### ❑ Return Value

E\_OK for normal completion or error code

### ❑ Error Code

E_ID	Invalid ID number (1)mplid<=0, VTMAX_MPL < mplid
E_CTX	Context error (invoked from an unallowed system state)

### ❑ Function

Resets the variable-sized memory pool indicated by mplid.

More specifically, this service call changes the status of all memory blocks in the variable-sized memory pool to an unused state and, if there is any task waiting to get a memory block, frees those tasks from the WAITING state. In this case, the task freed from the WAITING state will have error code EV\_RST returned to it.

Since all memory blocks are handled as in 'unused' state, once this service call is executed, the memory blocks previously acquired, if any, cannot be used.

This service call is the function outside  $\mu$ ITRON 4.0 specification.

## 5.23 Constants and Macros

### 5.23.1 Header Files

Constants and macros are defined in the header files shown below.

Figure 5.3 shows the relationship of how these files are included one from another.

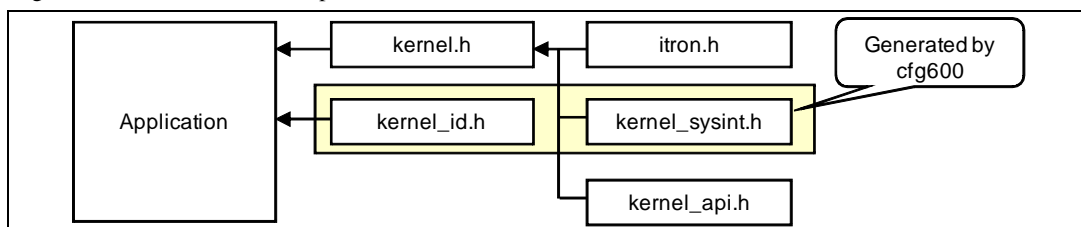


Figure 5.3 Include Relationship of Header Files

#### (1) kernel.h

Kernel.h is present in the "<installation directory>\inc600." Be sure kernel.h is included from the application.

It is in this kernel.h that kernel specifications are defined.

#### (2) kernel\_id.h

Kernel\_id.h is output by cfg600. Be sure kernel\_id.h is included from the application.

It is in this kernel\_id.h that the ID names, kernel configuration macros specified in the cfg file, proto-type declaration of tasks and hanlers, etc. are defined.

#### (3) kernel\_sysint.h

Kernel\_sysint.h is output by cfg600.

It is this kernel\_sysint.h that contains the definitions necessary to invoke service calls by an INT instruction.

#### (4) itron.h

Itron.h is present in the "<installation directory>\inc600".

It is in this itron.h that common definitions of ITRON specifications are defined.

#### (5) kernel\_api.h

Kernel\_api.h is present in the "<installation directory>\inc600".

It is in this kernel\_api.h that service call function declarations are written.

## 5.23.2 Content of Definition

Table 5.34 Constants and Macros

Classification	Macro	Definition	Where	Description
General	NULL	0	itron.h	Null pointer
	TRUE	1	itron.h	True
	FALSE	0	itron.h	False
	E_OK	0	itron.h	Normal completion
Object attribute	TA_NULL	0	itron.h	Object attributes unspecified
	TA_HLNG	0x0000	kernel.h	High-level language interface
	TA_ASM	0x0001	kernel.h	Assembly language interface
	TA_TFIFO	0x0000	kernel.h	Task queue in FIFO order
	TA_TPRI	0x0001	kernel.h	Task queue in order of task priority
	TA_MFIFO	0x0000	kernel.h	Message queue in FIFO order
	TA_MPRI	0x0002	kernel.h	Message queue in order of message priority
	TA_ACT	0x0002	kernel.h	Task is activated after creation
	TA_WSGL	0x0000	kernel.h	Do not allow multiple tasks to wait for eventflag
	TA_WMUL	0x0002	kernel.h	Allow multiple tasks to wait for eventflag
	TA_CLR	0x0004	kernel.h	Clear eventflag when freed from WAITING state
	TA_STA	0x0002	kernel.h	Create cyclic handler in operational state
TA_PHS	0x0004	kernel.h	Save cyclic handler phase	
Timeout	TMO_POL	0	kernel.h	Polling
	TMO_FEVR	-1	kernel.h	Waiting forever
Operation modes	TWF_ANDW	0x0000	kernel.h	Eventflag AND wait
	TWF_ORW	0x0001	kernel.h	Eventflag OR wait
Object states	TTS_RUN	0x0001	kernel.h	RUNNING state
	TTS_RDY	0x0002	kernel.h	READY state
	TTS_WAI	0x0004	kernel.h	WAITING state
	TTS_SUS	0x0008	kernel.h	SUSPENDED state
	TTS_WAS	0x000C	kernel.h	WAITING-SUSPENDED state
	TTS_DMT	0x0010	kernel.h	DORMANT state
	TTW_SLP	0x0001	kernel.h	Sleeping state
	TTW_DLY	0x0002	kernel.h	Delayed state
	TTW_SEM	0x0004	kernel.h	Waiting state for a semaphore resource
	TTW_FLG	0x0008	kernel.h	Waiting state for an eventflag
	TTW_SDTQ	0x0010	kernel.h	Sending waiting state for a data queue
	TTW_RDTQ	0x0020	kernel.h	Receiving waiting state for a data queue
	TTW_MBX	0x0040	kernel.h	Receiving waiting state for a mailbox
	TTW_MTX	0x0080	kernel.h	Waiting state for a mutex
	TTW_SMBF	0x0100	kernel.h	Sending waiting state for a message buffer
	TTW_RMBF	0x0200	kernel.h	Receiving waiting state for a message buffer
	TTW_MPF	0x2000	kernel.h	Waiting state for a fixed-sized memory block
	TTW_MPL	0x4000	kernel.h	Waiting state for a variable-sized memory block
	TCYC_STP	0x0000	kernel.h	Cyclic handler in non-operational state
	TCYC_STA	0x0001	kernel.h	Cyclic handler in operational state
TALM_STP	0x0000	kernel.h	Alarm handler in non-operational state	

Classification	Macro	Definition	Where	Description
Object states	TALM_STA	0x0001	kernel.h	Alarm handler in operational state
Other constants	TSK_SELF	0	kernel.h	Specify invoking task
	TSK_NONE	0	kernel.h	No relevant task
	TPRI_SELF	0	kernel.h	Specify base priority of invoking task
	TPRI_INI	0	kernel.h	Specify initial priority
Kernel configuration	TMIN_TPRI	1	kernel.h	Minimum task priority
	TMAX_TPRI	system.priority	kernel_id.h	Maximum task priority
	TMIN_MPRI	1	kernel.h	Minimum message priority
	TMAX_MPRI	system.message_pri	kernel_id.h	maximum message priority
	TKERNEL_MAKER	0x0115	kernel.h	Kernel maker code
	TKERNEL_PRID	0x0015	kernel.h	Identification number of the kernel
	TKERNEL_SPVER	0x5403	kernel.h	Version number of the ITRON specification
	TKERNEL_PRVER	0x0100	kernel.h	Version number of the kernel
	TMAX_ACTCNT	255	kernel.h	Maximum number of queued task activation requests
	TMAX_WUPCNT	255	kernel.h	Maximum number of queued task wakeup requests
	TMAX_SUSCNT	1	kernel.h	Maximum number of nested task suspension requests
	TBIT_FLGPTN	32	kernel.h	Number of bits in an eventflag
	TIC_NUME	system.tic_num	kernel_id.h	Time tick period numerator
	TIC_DENO	system.tic_deno	kernel_id.h	Time tick period denominator
	TMAX_MAXSEM	65535	kernel.h	Maximum value of the maximum semaphore resource count
	VTMAX_TSK	Number of "task[]"s	kernel_id.h	Maximum task ID
	VTMAX_SEM	Number of "semaphore[]"s	kernel_id.h	Maximum semaphore ID
	VTMAX_FLG	Number of "flag[]"s	kernel_id.h	Maximum eventflag ID
	VTMAX_DTQ	Number of "dataqueue[]"s	kernel_id.h	Maximum data queue ID
	VTMAX_MBX	Number of "mailbox[]"s	kernel_id.h	Maximum mailbox ID
	VTMAX_MTX	Number of "mutex[]"s	kernel_id.h	Maximum mutex ID
	VTMAX_MBF	Number of "message_buffer[]"s	kernel_id.h	Maximum message buffer ID
	VTMAX_MPF	Number of "memorypool[]"s	kernel_id.h	Maximum fixed-sized memory pool ID
	VTMAX_MPL	Number of "variable_memorypool[]"s	kernel_id.h	Maximum variable-sized memory pool ID
	VTMAX_CYH	Number of "cyclic_hand[]"s	kernel_id.h	Maximum cyclic handler ID
	VTMAX_ALH	Number of "alarm_hand[]"s	kernel_id.h	Maximum alarm handler ID
	VTSZ_MBFTBL	4	kernel.h	Size of message buffer's message management table
VTMAX_AREASIZE	0x2000000	kernel.h	Maximum size of various areas	
VTKNL_LVL	system.system_IPL	kernel_id.h	Kernel interrupt mask level	
VTIM_LVL	clock.IPL	kernel_id.h	Timer interrupt priority level	

Classification	Macro	Definition	Where	Description
Error codes	E_NOSPT	-11	itron.h	Unsupported function
	E_PAR	-17	itron.h	Parameter error
	E_ID	-18	itron.h	Invalid ID number
	E_CTX	-25	itron.h	Context error
	E_ILUSE	-28	itron.h	Illegal use of service call
	E_OBJ	-41	itron.h	Object state error
	E_QOVR	-43	itron.h	Queuing overflow
	E_RLWAI	-49	itron.h	Forced release from the WAITING state
	E_TMOUT	-50	itron.h	Polling failure or timeout
EV_RST	-127	itron.h	Released from WAITING state by the object reset	
Error code processing macros	ER ercd = ERCD(ER mercd, ER sercd)		itron.h	Generate an error code from the main error code (mercd) and sub-error code (sercd)
	ER mercd = MERCD(ER ercd)		itron.h	Retrieve the main error code from an error code
	ER sercd = SERCD(ER ercd)		itron.h	Retrieve the sub-error code from an error code



## 6. How to Write Application

### 6.1 Header Files

Include the following header files.

- kernel.h  
This is the header file of the kernel. kernel.h is stored in the "<installation directory>\inc600."
- kernel\_id.h  
kernel\_id.h is output by cfg600. It is in this kernel\_id.h that the various object names (xxx[].name), kernel configuration macros specified in the cfg file and prototype declaration of tasks and handlers are defined.  
The ID name can be used for the ID number that is passed to a service call, as shown below.  

```
ercd = act_tsk(ID_TASK1);
```

### 6.2 Handling of Variables

There is no relationship between the storage classes of variables in C language and the program types such as tasks and handlers under kernel specifications.

Table 6.1 shows how variables in C language are handled. For example, if it is possible that a global variable will be accessed from multiple tasks at the same time, exclusive control between those tasks is needed.

Table 6.1 Handling of Variables in C Language

No.	Storage class	Handling	Storage allocation
1	Global variables	Shared variables for all programs (tasks, handlers)	Static
2	Static variables outside function	Shared variables for the functions in one and the same file	Static
3	Auto variables, register variables, and static variables in function	Variables in the relevant function	Dynamic (stack)

## 6.3 Task

### 6.3.1 Registration in the Kernel

Registering tasks in the kernel is referred to as "task creation."

Task creation is accomplished by defining the task function start names and other information in task[] of the cfg file. For details, see Section 8.4.4, "Task Definition(task[])."

### 6.3.2 Coding

Figure 6.1 shows an example of how a task entry function is coded.

```
#include "kernel.h"
#include "kernel_id.h"
void task(VP_INT exinf) /* (1) */
{
    /* processing */ /* (2) */
    ext_tsk(); /* (3) */
}
```

Figure 6.1 Example of Coding a Task Entry Function

- (1) The APIs of task entry functions are as described in this manual. Note that the prototype declaration of the task entry function is output to kernel\_id.h by cfg600. If the task is initiated by sta\_tsk or ista\_tsk, start code (stacd) specified by sta\_tsk or ista\_tsk is passed to a parameter exinf. If the task is initiated by act\_tsk, iact\_tsk or task[].initial\_start=ON in the cfg file, task[].exinf is passed to a parameter exinf.
- (2) In the task, any service calls invocable from task context can be used.
- (3) Call ext\_tsk() at a place where the task needs to be terminated. Note that a return from the task entry function has the same effect as calling ext\_tsk().

A task entry function may also be written with an infinite loop, as shown in Figure 6.2.

```
#include "kernel.h"
#include "kernel_id.h"
void task(VP_INT exinf)
{
    for(;;) {
        /* processing */
    }
}
```

Figure 6.2 Example of Coding a Task Entry Function that Loops Infinitely

### 6.3.3 CPU State at Start

Since tasks are executed in user mode, privileged instructions cannot be used. For example, some facilities of the built-in functions supplied by the compiler, such as those provided in the header smachine.h, require caution because they use privileged instructions. In the assembler, however, there is a helpful facility (-chkpm option) that produces a warning when privileged instructions are used.

Note that when a task is activated, all interrupts in an enabled state.

Table 6.2 PSW at Start of Task

No.	Bit	Initial value	Description
1	IPL	0	All interrupts enabled
2	I	1	
3	PM	1	User mode
4	U	1	USP (user stack pointer)
5	Other bits	0	

If system.context includes "FPSW", the initial value of the FPSW register is 0x00000100.

## 6.4 Interrupt Handler

### 6.4.1 Registration in the Kernel

Registering interrupt handlers in the kernel is referred to as "definition of interrupt handlers."

Definition of interrupt handlers is accomplished by defining the handler entry function names and other information in `interrupt_vector[]` (for relocatable vectors) or `interrupt_fvector[]` (for fixed vectors) of the `cfg` file. For details, see Section 8.4.15, "Relocatable Vector Definition (`interrupt_vector[]`)," and Section 8.4.16, "Fixed Vector Definition (`interrupt_fvector[]`)."

### 6.4.2 Coding

Figure 6.3 shows an example of how an interrupt handler entry function is coded.

```
#include "kernel.h"
#include "kernel_id.h"
void int_handler(void) /* (1) */
{
    /* processing */ /* (2) */
} /* (3) */
```

Figure 6.3 Example of Coding an Interrupt Handler Entry Function

- (1) The APIs of interrupt handler entry functions are as described in this manual. The prototype declarations of interrupt handler entry functions are output to `kernel_id.h` by `cfg600`.
- (2) In the kernel interrupt handlers, it is possible to use the service calls invocable from non-task contexts. In the non-kernel interrupt handlers, however, service calls cannot be used.
- (3) When a handler entry function is compiled, if it is of the kernel interrupt type, an object code is generated that invokes the `ret_int` service call at the end of the handler.  
For non-kernel interrupt handlers, an object code is generated that causes the handler to be returned to the main at the end of it by an RTE instruction.  
For fast interrupt handlers, an object code is generated that causes the handler to be returned to the main at the end of it by an RTFI instruction.

### 6.4.3 CPU State at Start

The interrupt handlers are executed in supervisor mode.

As for the interrupt enable state, if "E" is specified for `interrupt_vector[].pragma_switch`, interrupts are masked with the relevant interrupt priority level.

On the other hand, if "E" is not specified for `pragma_switch`, and for the fixed vector interrupt case (`interrupt_fvector[]`), all interrupts are masked.

Table 6.3 PSW at Start of Interrupt Handler

No.	Bit	Initial value	Description
1	IPL	Relevant interrupt priority level	
2	I	<ul style="list-style-type: none"> <li>• "E" specified for <code>interrupt_vector[].pragma_switch</code>: 1</li> <li>• Other than above: 0</li> </ul>	
3	PM	0	Supervisor mode
4	U	0	ISP (interrupt stack pointer)
5	C,Z,S,O	Indeterminate	
6	Other bits	0	

## 6.5 Time Event Handlers (Cyclic handlers and Alarm Handlers)

### 6.5.1 Registration in the Kernel

Registering cyclic and alarm handlers in the kernel is referred to as "creation of cyclic handlers" and "creation of alarm handlers," respectively.

Creation of cyclic handlers is accomplished by defining the handler entry function names and other information in `cyclic_hand[]` of the `cfg` file. For details, see Section 8.4.13, "Cyclic Handler Definition (`cyclic_hand[]`)."

Creation of alarm handlers is accomplished by defining the handler entry function names and other information in `alarm_hand[]` of the `cfg` file. For details, see Section 8.4.14, "Alarm Handler Definition (`alarm_hand[]`)."

### 6.5.2 Coding

The method of coding the entry functions for cyclic and alarm handlers both are the same. Figure 6.4 shows an example of how a time event handler entry function is coded.

```
#include "kernel.h"
#include "kernel_id.h"
void time_handler(VP_INT exinf)    /* (1) */
{
    /* processing */                /* (2) */
}                                  /* (3) */
```

Figure 6.4 Example for Coding a Time Event Handler Entry Function

- (1) The APIs of time event handler entry functions are as described in this manual. Note that the prototype declarations of time event handler entry functions are output to `kernel_id.h` by `cfg600`. The value specified for `cyclic_hand[].exinf` (cyclic handler) or `alarm_hand[].exinf` (alarm handler) is passed to a parameter `exinf`.
- (2) In the time event handlers, it is possible to use the service calls invocable from non-task contexts.
- (3) The time event handlers are started by a call of function from the system clock interrupt handler in the kernel.

### 6.5.3 CPU State at Start

The time event handlers are executed in a context of the kernel's internal system clock interrupt handler.

The time event handlers are executed in supervisor mode.

As for the interrupt enable state, interrupts are masked with the timer interrupt level (clock.IPL).

Table 6.4 PSW at Start of Time Event Handler

No.	Bit	Initial value	Description
1	IPL	Timer interrupt level (clock.IPL)	
2	I	1	
3	PM	0	Supervisor mode
4	U	0	ISP (interrupt stack pointer)
5	C,Z,S,O	Indeterminate	
6	Other bits	0	

## 6.6 System-Down Routine

### 6.6.1 Summary

The system-down routine is a routine that is called when the system is down.

When one of the following phenomena occurs, a system-down results:

- Undefined interrupt generated
- vsys\_dwn or ivsys\_dwn service call issued
- Unlinked service call issued<sup>3</sup>
- Context error in ext\_tsk
- Context error in ret\_int

The system-down routine must always be created by the user.

### 6.6.2 Coding

Figure 6.5 shows an example of how a system-down routine entry function is coded.

```
#include "kernel.h"
#include "kernel_id.h"
void _RI_sys_dwn__(W type, VW inf1, VW inf2, VW inf3) /* (1) */
{
  /* processing */ /* (2) */
  while(1); /* (3) */
}
```

Figure 6.5 Example for Coding a System-Down Routine Entry Function

- (1) The APIs of system-down routine entry functions are as described in this manual. The function names are predetermined to be "\_RI\_sys\_dwn\_\_\_". Specifications of the parameters passed to the system-down routine are shown in Table 6.5.
- (2) No service calls can be invoked in the system-down routine.
- (3) In no case can the application return from the entry function of the system-down routine.

<sup>3</sup> Refer to 9.4, "Notes"



Table 6.5 Parameters Passed to the System-Down Routine

No.	Parameter	Register	Description
1	type	R1	<p>Error type</p> <p>(1) Error in ret_int : -1</p> <p>(2) Error in ext_tsk : -2</p> <p>(3) Unlinked service call issued : -3</p> <p>(4) Undefined relocatable interrupt : -16</p> <p>(5) Undefined fixed interrupt : -17</p> <p>(6) vsys_dwn, ivsys_dwn : Be sure to use a positive value.</p>
2	inf1	R2	<p>System abnormality information 1</p> <p>(1) Error in ret_int : E_CTX</p> <p>(2) Error in ext_tsk : E_CTX</p> <p>(3) Unlinked service call issued : E_NOSPT</p> <p>(4) Undefined relocatable/fixed interrupt :</p> <p>    (a) Does not use cfg600's -U option : Undefined</p> <p>    (b) Use cfg600's -U option : Vector number</p> <p>(5) vsys_dwn, ivsys_dwn : Any user-specified value</p>
3	inf2	R3	<p>System abnormality information 2</p> <p>(1) For errors in ret_int</p> <p>    2 : Invocation of ret_int from task context</p> <p>    3 : Invocation of ret_int from a PSW.IPL &gt; system.system_IPL state as with non-kernel interrupts</p> <p>    5 : Invocation of ret_int from the CPU-locked state</p> <p>(2) For errors in ext_tsk</p> <p>    1 : Invocation of ext_tsk from non-task context</p> <p>    4 : Invocation of ext_tsk from a PSW.IPL &gt; system.system_IPL state as with non-kernel interrupts</p> <p>(3) Unlinked service call issued : Indeterminate</p> <p>(4) Undefined relocatable/fixed interrupt : PC value stored to the stack by CPU's interrupt exception handling</p> <p>(5) vsys_dwn, ivsys_dwn : Any user-specified value</p>
4	inf3	R4	<p>System abnormality information 3</p> <p>(1) Error in ret_int: Indeterminate</p> <p>(2) Error in ext_tsk: Indeterminate</p> <p>(3) Unlinked service call issued : Indeterminate</p> <p>(4) Undefined relocatable/fixed interrupt : PSW value stored to the stack by CPU's interrupt exception handling</p> <p>(5) vsys_dwn, ivsys_dwn : Any user-specified value</p>

### 6.6.3 CPU State at Start

The system-down routine is executed in supervisor mode.

As for the interrupt enable state, interrupts are masked in the same way as when a system-down occurs.

Table 6.6 PSW at Start of System-Down Routine

No.	Bit	Initial value	Description
1	IPL	Same as for system-down	
2	I	0	
3	PM	0	Supervisor mode
4	U	0	ISP (interrupt stack pointer)
5	C,Z,S,O	Indeterminate	
6	Other bits	0	

## 6.7 Precautions to Take when Using Floating-Point Arithmetic Instructions

It is only when the `-fpu` option is specified that the compiler outputs floating-point arithmetic instructions. If the `-chkfpu` option is specified in the assembler, the floating-point arithmetic instructions written in a program are detected as warning.

### (1) When using floating-point arithmetic instructions in tasks

Make settings that include the FPSW in system.context of the `cfg` file.

The initial value of the FPSW is `0x00000100`. Please initialize FPSW if necessary.

### (2) When using floating-point arithmetic instructions in handlers

It is necessary that the handler explicitly guarantee the FPSW register. And the initial value of the FPSW is undefined. To guarantee and initialize the FPSW register, write a program as shown in Figure 6.6.

```
#include <machine.h>    // To use the compiler-supplied intrinsic function get_fpsw(), set_fpsw()
                        // includes machine.h

#include "kernel.h"
#include "kernel_id.h"

void handler(void)
{
    unsigned long old_fpsw; // Declares variable for saving the FPSW register
    old_fpsw = get_fpsw();  // Saves the FPSW register
    set_fpsw(0x00000100);  // Initialize FPSW if necessary
    /* Floating-point arithmetic operation */
    set_fpsw(old_fpsw);    // Restores the FPSW register
}
```

Figure 6.6 Program Example for a Handler that Uses Floating-Point Arithmetic Instructions

## 6.8 Precautions to Take when Using a Microcomputer that Supports the DSP Function

When a microcomputer which support the DSP function is used, it is necessary to note the treatment of the ACC register (accumulator)

Concretely, please note it as follows when you use the following instructions which update ACC register.

MACHI, MACLO, MULHI, MULLO, RACW, MVTACHI, MVTACLO

In no case does the compiler generate these instructions.

Note also that if the -chkdsp option is specified in the assembler, the DSP function instructions written in a program are detected as warning.

### (1) When using the above-mentioned instructions in tasks

Make settings that include ACC in system.context of the cfg file.

### (2) Handlers

If the application contains any tasks or handlers that use the above-mentioned instructions, it is necessary that all of the handlers explicitly guarantee the ACC register. Figure 6.7 shows an example of how to write a handler that guarantees the ACC register.

```

#include "kernel.h"
#include "kernel_id.h"

typedef struct {
    unsigned long upp; // bit63-32
    unsigned long mid; // bit47-16
} ST_ACC;

#pragma inline_asm(get_acc) // Macro to save the ACC register
void get_acc(ST_ACC *pk_acc)
{
    mvfachi r5
    mov.l r5,[r1]
    mvfacmi r5
    mov.l r5,4[r1]
}

#pragma inline_asm(set_acc) // Macro to restore the ACC register
void set_acc(ST_ACC *pk_acc)
{
    mov.l [r1],r5
    mvtachi r5
    mov.l 4[r1],r5
    shll #16,r5
    mvtaclo r5
}

void handler(void)
{
    ST_ACC st_acc; // Declares variable for saving the ACC register
    get_acc(&st_acc); // Saves the ACC register
    /* processing */
    set_acc(st_acc); // Restores the ACC register
}

```

Figure 6.7 Example of a Handler that Guarantees the ACC Register

---

## 7. Procedure for Generating the Load Module

---

### 7.1 Summary

The application programs for the RI600/4 are generally developed following the procedure described below.

#### (1) Generating a project

To use High-performance Embedded Workshop, create a new project that uses the RI600/4 in High-performance Embedded Workshop.

#### (2) Coding the application program

Code the application program. Correct the sample startup program as necessary.

#### (3) Creating a configuration file (cfg file)

Using a text editor, etc., create a cfg file that defines task entry addresses and stack sizes. The GUI configurator may also be used to create a cfg file.

#### (4) Executing the command line configurator (cfg600)

cfg600 loads the cfg file, from which it generates system data definition files (e.g., kernel\_rom.h, kernel\_ram.h) and include files for the application (e.g., kernel\_id.h).

#### (5) Generating the load module

Execute the make command or execute a build in High-performance Embedded Workshop to generate the load module.

Figure 7.1 shows a flowchart, following which a load module is generated.

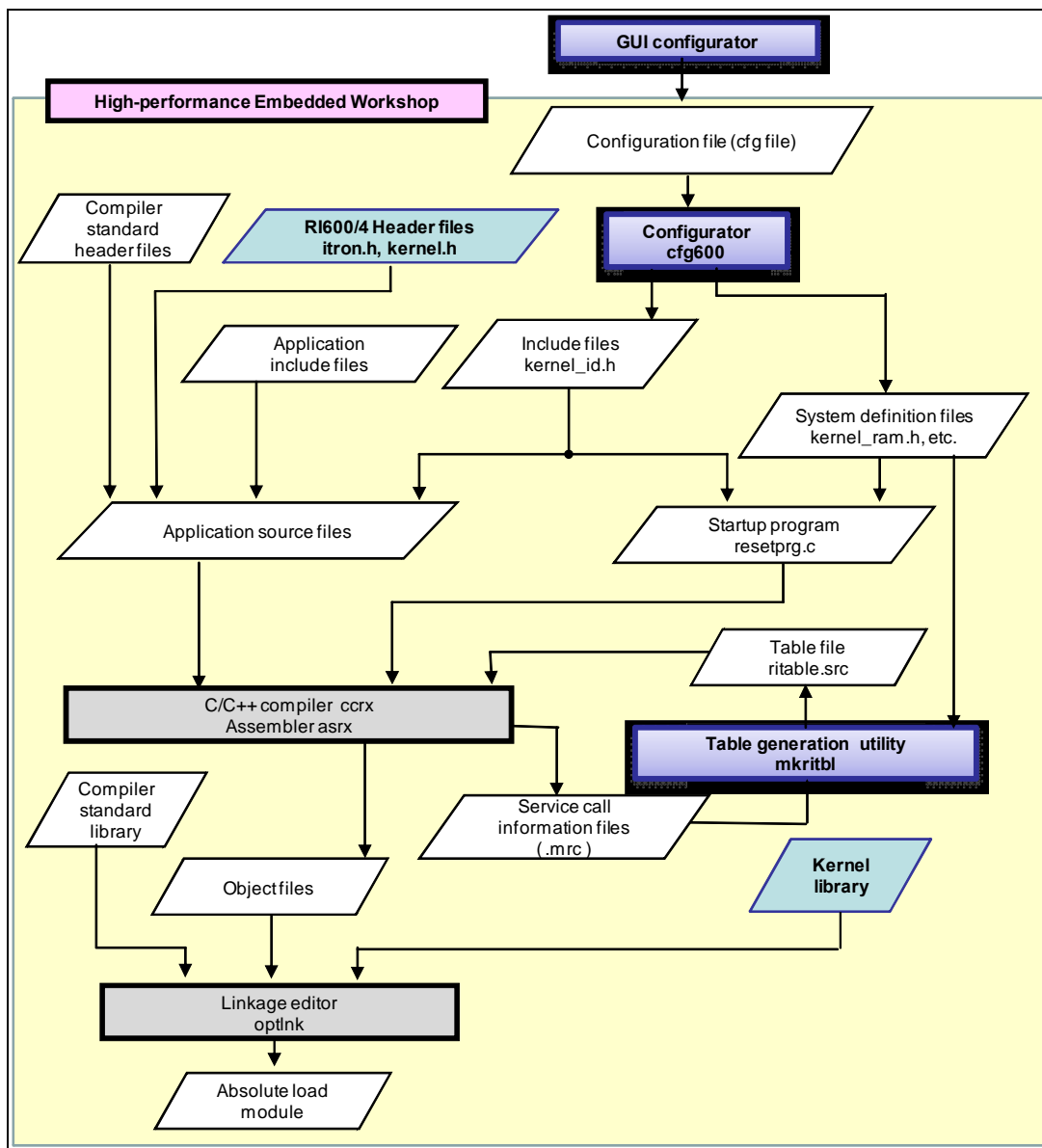


Figure 7.1 Flowchart of Load Module Generation

## 7.2 Creating Startup File (resetprg.c)

The startup file includes following statements. Note, it usually makes it to resetprg.c though the file name is arbitrary.

- (1) Startup program (PowerON\_Reset\_PC())
- (2) System-down routine (\_RI\_sys\_dwn\_\_())
- (3) Getting kernel\_rom.h and kernel\_ram.h

### (1) Startup Program (PowerON\_Reset\_PC())

The startup program is the program which is register in the reset vector. The startup program executes in the supervisor mode.

The startup program usually does the following processing.

- Initializes the processor and hardware  
If the high-speed interrupt function is used, it is necessary to initialize FINTV register.
- Initializes the execution environment for C/C++ language software (for example, by initializing sections)
- Initializes the system timer  
If CMT0, CMT1, CMT2, or CMT3 is specified for clock.timer, includes ri\_cmt.h file which is generated by cfg600, and call "void \_RI\_init\_cmt(void)".
- Start kernel (call ivsta\_knl())

Please maintain the state that any interrupt is not accepted until calling vsta\_knl. Note, PSW.I at reset is 0 (all interrupts are masked).

The function name of the startup program is usually made "void PowerON\_Reset\_PC(void)". It is necessary to define the function name in interrupt\_fvector[31] when assuming the function name excluding this.

It is necessary to declare "#pragma entry PowerON\_Reset\_PC". The compiler generates the object code to initialize stack pointer (ISP) by this declaration and "#pragma stacksize" declaration in the kernel\_ram.h which is generated by cfg600.

### (2) System-Down Routine (\_RI\_sys\_dwn\_\_())

Refer to 6.6, "System-Down Routine."



### (3) Getting kernel\_rom.h and kernel\_ram.h Included

The kernel\_rom.h and kernel\_ram.h are the system definition files generated by cfg600. These files contain definitions of various data areas, etc.

The startup file (resetprg.c) must include these files in the following order.

```
#include "kernel.h"      /* provided by RI600-4 */
#include "kernel_id.h"   /* generated by cfg600 */
#include "kernel_ram.h"  /* generated by cfg600 */
#include "kernel_rom.h"  /* generated by cfg600 */
```

### (4) Compiler option

It is necessary to specify "-nostuff" option for the startup file.

### (5) Example of the startup file

```
1.  #include <machine.h>
2.  #include <_h_c_lib.h>
3.  // #include <stddef.h>           // Remove the comment when you use errno
4.  // #include <stdlib.h>          // Remove the comment when you use rand()
5.  #include "typedefine.h"
6.  #include "kernel.h"           // Provided by RI600/4
7.  #include "kernel_id.h"       // Generated by cfg600
8.
9.  #if (((_RI_CLOCK_TIMER) >=0) && ((_RI_CLOCK_TIMER) <= 3))
10. #include "ri_cmt.h"           // Generated by cfg600
11.                               // Do comment-out when clock.timer is either NOTIMER or OTHER.
12. #endif
13.
14. #ifdef __cplusplus
15. extern "C" {
16. #endif
17. void PowerON_Reset_PC(void);
18. void _RI_sys_dwn__( W type, VW inf1, VW inf2, VW inf3 );
19. #ifdef __cplusplus
20. }
21. #endif
22.
23. #ifdef __cplusplus           // Use SIM I/O
24. extern "C" {
25. #endif
26. extern void _INIT_IOLIB(void);
27. extern void _CLOSEALL(void);
```

```

28.  #ifndef __cplusplus
29.  }
30.  #endif
31.
32.  #define FPSW_init 0x00000100
33.
34.  //extern void srand(_UINT); // Remove the comment when you use rand()
35.  //extern _SBYTE *_slptr; // Remove the comment when you use strtok()
36.
37.  #ifndef __cplusplus // Use Hardware Setup
38.  extern "C" {
39.  #endif
40.  extern void HardwareSetup(void);
41.  #ifndef __cplusplus
42.  }
43.  #endif
44.
45.  // #ifndef __cplusplus // Remove the comment when you use global class object
46.  // extern "C" { // Sections C$INIT and C$END will be generated
47.  // #endif
48.  // extern void _CALL_INIT(void);
49.  // extern void _CALL_END(void);
50.  // #ifndef __cplusplus
51.  // }
52.  // #endif
53.
54.  #pragma section ResetPRG
55.
56.  #pragma entry PowerON_Reset_PC
57.
58.  ////////////////////////////////////////////////////////////////////
59.  // Power-on Reset Program
60.  ////////////////////////////////////////////////////////////////////
61.  void PowerON_Reset_PC(void)
62.  {
63.      set_fpsw(FPSW_init);
64.
65.      _INITSC1();
66.
67.      _INIT_IOLIB(); // Use SIM I/O
68.
69.      // ermo=0; // Remove the comment when you use ermo
70.      // srand((_UINT)1); // Remove the comment when you use rand()

```

```

71. // _slptr=NULL;           // Remove the comment when you use strtok()
72.
73.   HardwareSetup();       // Use Hardware Setup
74.
75. // set_fintv(<handler address>); // Initialize FINTV register
76.
77.
78. #if (((_RI_CLOCK_TIMER) >=0) && ((_RI_CLOCK_TIMER) <= 3))
79.   _RI_init_cmt();        // Initialize CMT for RI600/4
80.                           // Do comment-out when clock.timer is either NOTIMER or OTHER.
81. #endif
82.
83.   nop();
84.
85. // _CALL_INIT();         // Remove the comment when you use global class object
86.
87.   vsta_knl();           // Start RI600/4
88.                           // Never return from vsta_knl
89.
90.   _CLOSEALL();         // Use SIM I/O
91.
92. // _CALL_END();         // Remove the comment when you use global class object
93.
94.   brk();
95.
96. }
97.
98. ////////////////////////////////////////////////////////////////////
99. // System-down routine for RI600/4
100. ////////////////////////////////////////////////////////////////////
101. #pragma section P PRI_KERNEL
102. #pragma section B BRI_RAM
103. struct SYSDWN_INF{
104.   W type;
105.   VW inf1;
106.   VW inf2;
107.   VW inf3;
108. };
109.
110. volatile struct SYSDWN_INF _RI_sysdwn_inf;
111.
112. void _RI_sys_dwn__( W type, VW inf1, VW inf2, VW inf3 )
113. {

```

```
114. // Now PSW.I=0 (all interrupts are masked.)
115.
116.  _RI_sysdwn_inf.type = type;
117.  _RI_sysdwn_inf.inf1 = inf1;
118.  _RI_sysdwn_inf.inf2 = inf2;
119.  _RI_sysdwn_inf.inf3 = inf3;
120.
121.  while(1)
122.  ;
123. }
124.
125. ////////////////////////////////////////////////////////////////////
126. // RI600/4 system data
127. ////////////////////////////////////////////////////////////////////
128. #include "kernel_ram.h" // generated by cfg600
129. #include "kernel_rom.h" // generated by cfg600
```

## 7.3 Kernel Libraries

The kernel library consists of ri600lit.lib for use in little-endian form and ri600big.lib for use in big-endian form. These libraries are stored in the "<installation directory>\lib600."

Please use either of libraries according to endian type of the MCU (MDE pin).

## 7.4 Section List

The RI600/4 uses the sections described below. The user must allocate each section at a suitable address at linkage.

When the external memory which endian type is different from the MCU's endian type (MDE pin), do not locate the following sections to the external memory.

- **PRI\_KERNEL**  
This is the kernel's program section.  
The section attribute is "CODE", and the alignment number is 1.
- **CRI\_ROM**  
This is the kernel's constant data section.  
The section attribute is "ROMDATA", and the alignment number is 4.
- **FIX\_INTERRUPT\_VECTOR**  
This is a section for the fixed interrupt vector table. This section must be mapped to the address 0xFFFFF80.  
The section attribute is "ROMDATA", and the alignment number is 4.
- **INTERRUPT\_VECTOR**  
This is a section for the relocatable interrupt vector table.  
The section attribute is "ROMDATA", and the alignment number is 4.
- **SI**  
This is a section for the system stack.  
The section attribute is "DATA", and the alignment number is 4.
- **SURI\_STACK** section (Task stack)  
The section name assigned to the stack for tasks normally is specified in task[].stack\_section of the cfg file. When the stack\_section is omitted, SURI\_STACK is applied as the section name.  
The section attribute is "DATA", and the alignment number is 4.
- **BRI\_RAM** section  
This is a section for the kernel variables.  
The section attribute is "DATA", and the alignment number is 4.
- **BRI\_HEAP** section (Message buffer, Fixed-sized memory pool, Variable-sized memory pool)  
The section name assigned to these areas normally is specified in the corresponding definitions made in the cfg file. When this is omitted, BRI\_HEAP is applied as the section name.  
The section attribute is "DATA", and the alignment number is 4.

## 7.5 Service Call Information File (mrc file) and Essential Compiler Option

Service call information files (mrc files) are generated by compiling application source files including "kernel.h".

The name of service calls that the source file uses is output to mrc file.

The mrc file should be inputted to mkritbl.

Please input mrc files generated at making library to mkritbl when you make library.

The "-ri600\_preinit\_mrc" compiler option should be specified for application files which includes "kernel.h". Service call modules that application does not use might be linked though the problem is not caused in run-time even if this option is not specified.

## 7.6 Processor Mode

Tasks are executed in user mode (PSW.PM=1). Handlers are executed in supervisor mode (PSW.PM=0).

The CPU detects privileged instruction exception when a privileged instruction is executed in user mode.

In the program executed in user mode, please do not use a privileged instruction.

Privileged instructions are used in the following cases.

- Uses intrinsic functions which are provided by "smachine.h".
- Writes privileged instructions in assembly source programs

The assembler supports "-chkpm" option which detects privileged instruction as warning, and uses this option if necessary.

---

## 8. Configurator (cfg600)

---

### 8.1 Creating a Configuration File (cfg File)

The OS resources used in the application must be registered with the RI600/4 system. A configuration file (cfg file) is where these settings are made, and the tool used for registration with the system is the configurator (cfg600).

Based on the content defined in a configuration file (cfg file), cfg600 generates the files needed to build the kernel.

### 8.2 Representation Format in cfg File

This section describes the representation format of the definition data in the cfg file.

#### (1) Comment Statement

A statement from a double slash (//) to the end of a line is handled as a comment and no processing is applied.

#### (2) End of Statement

A statement must end with a semicolon (;).

#### (3) Numeric Value

A numeric value must be written in one of the following formats.

- Hexadecimal  
Add "0x" or "0X" at the beginning of a numeric value or add "h" or "H" at the end. In the latter format, be sure to add "0" at the beginning when the value begins with an alphabetic letter from A to F or a to f. Note that the configurator does not distinguish between uppercase and lowercase letters for alphabetic letters (A to F or a to f) used in numeric value representation.<sup>4</sup>
- Decimal  
Simply write an integer value as is usually done (23, for example). Note that a decimal value must not begin with "0".
- Octal  
Add "0" at the beginning of a numeric value or add "O" or "o" at the end.
- Binary  
Add "B" or "b" at the end of a numeric value. Note that a binary value must not begin with "0".

---

<sup>4</sup> The configurator distinguishes uppercase and lowercase letters except for 'A' to 'F' and 'a' to 'f' in numeric value representation.

Table 8.1 Examples of Numeric Value Representation

Hexadecimal	0xf12 0Xf12 0a12h 0a12H 12h 12H
Decimal	32
Octal	017 17o 17O
Binary	101110b 101010B

A numeric value can include operators. Table 8.2 shows the available operators.

Table 8.2 Operators

Operator	Precedence	Direction of Computation
()	High	Left to right
- (unary minus)		Right to left
* / %		Left to right
+ - (binary minus)	Low	Left to right

The following are examples of numeric values.

- 123
- 123 + 0x23
- (23/4 + 3) \* 2
- 100B + 0aH

A numeric value greater than 0xFFFFFFFF must not be specified.

#### (4) Symbol

A symbol is a string of numeric characters, uppercase alphabetic letters, lowercase alphabetic letters, and underscores (\_). It must not begin with a numeric character.

The following are examples of symbols.

- \_TASK1
- IDLE3



### (5) Function Name

A function name consists of numeric characters, uppercase alphabetic letters, lowercase alphabetic letters, underscores (\_), and dollar signs (\$). It must not begin with a numeric character and must end with "()".

The following are examples of function names.

- main()
- func()

To specify module name written by assembly language, name to start the start label with '\_', and specify the name that excludes '\_' for function name.

### (6) Frequency

The frequency is indicated by a character string that consist of numerals and . (period), and ends with MHz. The numerical values are significant up to six decimal places. Also note that the frequency can be entered using decimal numbers only.

Frequency entry examples are presented below.

- 16MHz
- 8.1234MHz

It is also well to remember that the frequency must not begin with . (period).

## 8.3 Default cfg File

For most definition items, if the user omits settings, the settings in the default cfg file are used.

The default cfg file is stored in the directory indicated by environment variable "LIB600". Be sure not to edit this file.

## 8.4 Definition Items in cfg File

The following items should be defined in the cfg file.

- System definition (system)
- System clock definition (clock)
- Task definition (task[])
- Semaphore definition (semaphore[])
- Eventflag definition (flag[])
- Data queue definition (dataqueue[])
- Mailbox definition (mailbox[])
- Mutex definition (mutex[])
- Message buffer definition (message\_buffer[])
- Fixed-sized memory pool definition (memorypool[])
- Variable-sized memory pool definition (variable\_memorypool[])
- Cyclic handler definition (cyclic\_hand[])
- Alarm handler definition (alarm\_hand[])
- Relocatable interrupt vector definition (interrupt\_vector[])
- Fixed interrupt vector definition (interrupt\_fvector[])

## 8.4.1 System Definition (system)

Here, define the general information relating to the kernel system. In this definition, system cannot be omitted.

### Format

```
system {
    stack_size           = (1) System stack size;
    priority             = (2) Maximum value of task priority;
    system_IPL          = (3) Kernel interrupt mask level;
    message_pri         = (4) Maximum value of message priority;
    tic_deno            = (5) Time tick denominator;
    tic_num             = (6) Time tick numerator;
    context             = (7) Task context register;
};
```

### Contents

#### (1) System stack size (stack\_size)

**Description:** Define the total stack size used in service call processing and interrupt processing.

**Definition format:** Numeric value

**Definition range:** Multiple of 4 of 8 or more

**When omitting:** The set value in default cfg file (factory setting: 0x800) applied

#### (2) Maximum value of task priority (priority)

**Description:** Define the maximum value of task priority used in the application.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** The set value in default cfg file (factory setting: 32) applied

#### (3) Kernel interrupt mask level (system\_IPL)

**Description:** Define the interrupt mask level when the kernel's critical section is executed (PSW register's IPL value). Interrupts with higher priority levels than that are handled as "non-kernel" interrupts.

**Definition format:** Numeric value

**Definition range:** 1 - 15

**When omitting:** The set value in default cfg file (factory setting: 7) applied

#### (4) Maximum value of message priority (message\_pri)

**Description:** Define the maximum value of message priority used in the mailbox function. Note that if the mailbox function is unused, this definition item has no effect.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** The set value in default cfg file (factory setting: 255) applied

**(5) Time tick denominator (tic\_deno)**

**Description:** Define the denominator of the time tick. At least one of the time tick numerator or denominator must be 1.

The time tick time (kernel timer interrupt cycle) is calculated by the equation below.

$$\text{Time tick time (in millisecond)} = \text{tic\_nume} / \text{tic\_deno}$$

No matter how tic\_nume and tic\_deno are set, the units of time in which units service calls are handled is always milliseconds (millisecond). It is by tic\_nume and tic\_deno that the accuracy of the time that the kernel manages is determined.

**Definition format:** Numeric value

**Definition range:** 1 - 100

**When omitting:** The set value in default cfg file (factory setting: 1) applied

**(6) Time tick numerator (tic\_nume)**

**Description:** Define the numerator of the time tick. For details, see the preceding item.

**Definition format:** Numeric value

**Definition range:** 1 - 65535

**When omitting:** The set value in default cfg file (factory setting: 1) applied

**(7) Task context register (context)**

**Description:** Define the register set used by tasks. The settings made here apply to all tasks.

**Definition format:** Symbol

**Definition range:** Select one from Table 8.3.

Table 8.3 system.context

Set value	Registers guaranteed as task context			
	CPU		FPU	DSP
	PSW, PC, R0 - R7, R14, R15	R8 - R13	FPSW	ACC
NO	√	√		
FPSW	√	√	√	
ACC	√	√		√
FPSW,ACC	√	√	√	√
MIN	√			
MIN,FPSW	√		√	
MIN,ACC	√			√
MIN,FPSW,ACC	√		√	√

**When omitting:** The set value in default cfg file (factory setting: NO) applied

**Remark:** For system.context, please be sure to see Section 8.4.2, "Precautions to Take when Defining system.context."

## 8.4.2 Precautions to Take when Defining system.context

### (1) Precautions regarding the FPU and ACC (accumulator)

The value to be set for system.context differs depending on how the FPU and DSP are handled.

Please set system.context appropriately according to the following explanations.

Note, if system.context is set to other than recommended value, the kernel performance may be slightly deteriorated, compared to the recommended settings case.

**Remark:** The compiler outputs floating-point arithmetic instructions only when the -fpu option is specified. If the -chkfpu option is specified in the assembler, the floating-point arithmetic instructions written in a program are detected as warning.

In no case does the compiler output the DSP function instructions. If the -chkdsp option is specified in the assembler, the DSP function instructions written in a program are detected as warning.

#### (a) When using a microcomputer that incorporates the FPU and the DSP (accumulator)

Table 8.4 When using a microcomputer that incorporates the FPU and the DSP (accumulator)

Floating-point arithmetic instructions in tasks	DSP function instructions in tasks	system.context
Yes	Yes	FPSW- and ACC- included settings essential
Yes	No	FPSW-included setting essential and ACC-excluded setting recommended
No	Yes	ACC-included setting essential and FPSW-excluded setting recommended
No	No	FPSW- and ACC- excluded settings recommended

#### (b) When using a microcomputer that incorporates the FPU, but does not contain the DSP (accumulator)

Table 8.5 When using a microcomputer that incorporates the FPU, but does not contain the DSP (accumulator)

Floating-point arithmetic instructions in tasks	DSP function instructions in tasks	system.context
Yes	Yes	DSP function instructions cannot be used.
Yes	No	FPSW-included and ACC-excluded settings essential
No	Yes	DSP function instructions cannot be used.
No	No	ACC-excluded setting essential and FPSW-excluded setting recommended

**(c) When using a microcomputer that does not incorporate the FPU, but contains the DSP (accumulator)**

Table 8.6 When using a microcomputer that does not incorporate the FPU, but contains the DSP (accumulator)

Floating-point arithmetic instructions in tasks	DSP function instructions in tasks	system.context
Yes	Yes	Floating-point arithmetic instructions cannot be used.
Yes	No	
No	Yes	FPSW-excluded and ACC-included settings essential
No	No	ACC-excluded setting essential and FPSW-excluded setting recommended

**(d) When using a microcomputer that incorporates neither the FPU nor the DSP (accumulator)**

Table 8.7 When using a microcomputer that incorporates neither the FPU nor the DSP (accumulator)

Floating-point arithmetic instructions in tasks	DSP function instructions in tasks	system.context
Yes	Yes	Floating-point arithmetic instructions and DSP function instructions cannot be used.
Yes	No	
No	Yes	
No	No	FPSW- and ACC-excluded settings essential

**(2) Relationship with the compiler options `fint_register` and `base`**

In `system.context`, by selecting one of choices "MIN," "MIN, ACC," "MIN, FPSW," or "MIN, ACC, FPSW," it is possible to configure the registers so that R8–R13 registers will not be saved as task contexts. This results in an increased processing speed.

Note, however, that such a setting of `system.context` is permitted in only the case where all of R8–R13 registers are specified to be used by the compiler options `fint_register` and `base`. For example, the following cases of option specification apply to this:

Good example:

Example 1: `-fint_register=4 -base=rom=R8 -base=ram=R9`

Example 2: `-fint_register=3 -base=rom=R8 -base=ram=R9 -base=0x80000=R10`

If, in any other case, the above setting is made for `system.context`, the kernel will not operate normally. For example, the following cases of option specification apply to this:

Bad example:

Example 3: No `fint_register` and `base` options

Example 4: `-fint_register=4`

Example 5: `-base=rom=R8 -base=ram=R9`

Example 6: `-fint_register=3 -base=rom=R8 -base=ram=R9`

### 8.4.3 System Clock Definition (clock)

Define the clock frequency and other information relating to the system clock.

#### Format

```
clock {
    timer           = (1) Selection of the system timer;
    template        = (2) Template file;
    timer_clock     = (3) System timer clock frequency;
    IPL             = (4) Timer interrupt priority level;
};
```

#### Contents

##### (1) Selection of the system timer (timer)

**Description:** Define the hardware timer used for the system clock.

**Definition format:** Symbol

**Definition range:** Select one out of the following. If one of CMT0, CMT1, CMT2, or CMT3 is specified, cfg600 generates the timer driver source code (ri\_cmt.h).

- CMT0: Uses the microcomputer's internal CMT channel 0.
- CMT1: Uses the microcomputer's internal CMT channel 1.
- CMT2: Uses the microcomputer's internal CMT channel 2.
- CMT3: Uses the microcomputer's internal CMT channel 3.
- OTHER: Uses a timer other than the above. In this case, the user needs to create a timer initialize routine.
- NOTIMER: Does not use the system timer function.

**When omitting:** The set value in default cfg file (factory setting: CMT0) applied

##### (2) Template file (template)

**Description:** Specify template file where hardware information and initialization function of CMT is described.

This definition is ignored when one of NOTIMER or OTHER is specified for clock.timer.

Application must call "void \_RI\_init\_cmt(void)" before starting kernel when one of CMT0, CMT1, CMT2, or CMT3 is specified for clock.timer. To call \_RI\_init\_cmt(), includes ri\_cmt.h generated by cfg600. And this function must call with all the interruptions prohibited. Normally, PowerON\_Reset\_PC() in resetprg.c calls \_RI\_init\_cmt().

The template files are provided by RI600/4. The RI600/4 V.1.00 provides only "rx610.tpl". The template files might be added by the version in the future.

Note no correspondence about template file name and MCU type No. For example, "rx610.tpl" might be able to use for MCU other than RX610 group. Please refer to the release note of the product attachment for the relation between template files and MCU type No.

Either CMT0, CMT1, CMT2 or CMT3 might be unsupported according to template file. When unsupported CMT channel is specified for clock.timer, the cfg600 does not detect error but ri\_cmt.h detect error at compilation.

**Definition format:** Symbol

**Definition range:** -

**When omitting:** The set value in default cfg file (factory setting: rx610.tpl) applied

### (3) System timer clock frequency (timer\_clock)

**Description:** Define the frequency of the clock supplied to the system timer.

If one of CMT0, CMT1, CMT2, or CMT3 is selected for timer, specify the frequency of the PCLK (peripheral module clock).

**Definition format:** Frequency

**Definition range:** -

**When omitting:** The set value in default cfg file (factory setting: 25MHz) applied

### (4) Timer interrupt priority level (IPL)

**Description:** Define the interrupt priority level of the system timer. Interrupts with lower priority levels than the one defined here are not accepted while the system timer interrupt handler is being executed.

**Definition format:** Numeric value

**Definition range:** 1 - system.system\_IPL

**When omitting:** The set value in default cfg file (factory setting: 4) applied

### (5) Points of concern for timer=OTHER

The following actions are required.

1. Initialize the timer before starting the kernel (vsta\_knl).  
The cfg600 outputs following macros to the "kernel\_id.h". Please initialize the timer based on this information.
  - `_RI_CLOCK_IPL` : Timer interrupt priority level (clock.IPL)
  - `TIC_DENO` : Time tick denominator (system.tic\_deno)
  - `TIC_NUME` : Time tick numerator (system.tic\_nume)

2. Define the relocatable interrupt vector as follows.

```
interrupt_vector [<Vector number>] {
    entry_address = _RI_SYS_STMR_INH;
    os_int = YES;
};
```



## 8.4.4 Task Definition(task[])

The definition item task[] is provided for the definition (creation) of tasks.

Note that in specifications of the product described herein there isn't any particular task something like an initial startup task. When defining a task in the cfg file, specify ON for task[].initial\_start, and the task will automatically go to the READY state when the system starts. When multiple task[].initial\_start are ON, they go to the READY state in small order of its ID number.

At least one task[] definition with initial\_start=ON is necessary in the cfg file.

### Format

```
task[(1) ID number] {
    name                = [(2) ID name];
    entry_address       = [(3) Task entry address];
    stack_size          = [(4) User stack size of task];
    stack_section       = [(5) Section name assigned to the stack area];
    priority             = [(6) Initial priority of task];
    initial_start       = [(7) TA_ACT attribute (initial state after creation)];
    exinf               = [(8) Extended information];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Task entry address (entry\_address)

**Description:** Define the entry address of the task starting from which it is executed.

**Definition format:** Function name

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (4) User stack size of task (stack\_size)

**Description:** Define the user stack size of the task. The user stack refers to the stack area that each task uses. The RI600/4 requires that tasks be assigned a user stack individually.

The user stack area of a size specified here is generated by cfg600.

**Definition format:** Numeric value

**Definition range:** Multiple of 4 of 44 or more

**When omitting:** The set value in default cfg file (factory setting: 256) applied

#### (5) Section name assigned to the stack area (stack\_section)

**Description:** Define the section name to be assigned to the user stack area. The section attribute is "DATA", and the alignment number is 4. When linking, be sure to locate this section in the RAM area.

**Definition format:** Symbol

**Definition range:** -

**When omitting:** The set value in default cfg file (factory setting: SURI\_STACK) applied

#### (6) Task initial priority (priority)

**Description:** Define the task initial priority.

**Definition format:** Numeric value

**Definition range:** 1 - system.priority

**When omitting:** The set value in default cfg file (factory setting: 1) applied

#### (7) TA\_ACT attribute (initial state after creation) (initial\_start)

**Description:** Define the initial state of the task that is either the READY state or a DORMANT state. This definition item corresponds to the task's TA\_ACT attribute.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- ON : Placed in the READY state at kernel startup
- OFF : Placed in DORMANT state at kernel startup

**When omitting:** The set value in default cfg file (factory setting: OFF) applied

#### (8) Extended information (exinf)

**Description:** Define the extended information of the task.

**Definition format:** Numeric value

**Definition range:** 0 - 0xFFFFFFFF

**When omitting:** The set value in default cfg file (factory setting: 0) applied

## 8.4.5 Semaphore Definition (semaphore[])

The definition item semaphore[] is provided for the definition (creation) of semaphores.

### Format

```
semaphore[(1) ID number] {
    name           = [(2) ID name];
    max_count      = [(3) Maximum value of semaphore counter];
    initial_count  = [(4) initial value of semaphore counter];
    wait_queue     = [(5) Queue attribute];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Maximum value of semaphore counter (max\_count)

**Description:** Define the maximum value of the semaphore counter.

**Definition format:** Numeric value

**Definition range:** 1 - 65535

**When omitting:** The set value in default cfg file (factory setting: 1) applied

#### (4) Initial value of semaphore counter (initial\_count)

**Description:** Define the initial value of the semaphore counter.

**Definition format:** Numeric value

**Definition range:** 0 to max\_count

**When omitting:** The set value in default cfg file (factory setting: 1) applied

**(5) Queue attribute (wait\_queue)**

**Description:** Define the queue attribute regarding how tasks are queued waiting for the semaphore.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_TFIFO : Queued in FIFO order
- TA\_TPRI : Queued in order of task priority

**When omitting:** The set value in default cfg file (factory setting: TA\_TFIFO) applied

## 8.4.6 Eventflag Definition (flag[])

The definition item flag[] is provided for the definition (creation) of eventflags.

### Format

```
flag[(1) ID number] {
    name = [(2) ID name];
    initial_pattern = [(3) Initial bit pattern of eventflag];
    wait_queue = [(4) Queue attribute];
    wait_multi = [(5) Multiple wait permission attribute];
    clear_attribute = [(6) Clear attribute];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Initial bit pattern of eventflag (initial\_pattern)

**Description:** Define the initial bit pattern of the eventflag.

**Definition format:** Numeric value

**Definition range:** 0 - 0xFFFFFFFF

**When omitting:** The set value in default cfg file (factory setting: 0) applied

#### (4) Queue attribute (wait\_queue)

**Description:** Define the queue attribute regarding how tasks are queued waiting for the eventflag.

Note that if TA\_WSGL is specified for wait\_multi, this definition item has no effect. Also, even in the case where TA\_WMUL is specified for wait\_multi, if clear\_attribute is chosen to be NO, the queue is managed in FIFO order regardless of how this definition item is specified.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_TFIFO : Queued in FIFO order
- TA\_TPRI : Queued in order of task priority

**When omitting:** The set value in default cfg file (factory setting: TA\_TFIFO) applied

#### (5) Multiple wait permission attribute (wait\_multi)

**Description:** Define the attribute regarding whether multiple tasks are permitted to wait for the eventflag.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_WMUL : Multiple tasks are permitted to wait
- TA\_WSGL : Multiple tasks not permitted to wait

**When omitting:** The set value in default cfg file (factory setting: TA\_WSGL) applied

#### (6) Clear attribute (clear\_attribute)

**Description:** Define the clear attribute (TA\_CLR) of the eventflag.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- YES : Clear attribute set
- NO : Clear attribute not set

**When omitting:** The set value in default cfg file (factory setting: NO) applied

## 8.4.7 Datq Queue Definition (dataqueue[])

The definition item dataqueue[] is provided for the definition (creation) of data queues.

### Format

```
dataqueue[(1) ID number] {
    name           = [(2) ID name];
    buffer_size    = [(3) Maximum data count of the data queue];
    wait_queue     = [(4) Queue attribute];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Maximum data count of the data queue (buffer\_size)

**Description:** Define the maximum number of data in the data queue. The size of data queue area is  $\text{buffer\_size} \times 4$  (bytes).

A data queue with data count = 0 can be created.

**Definition format:** Numeric value

**Definition range:** 0 - 65535

**When omitting:** The set value in default cfg file (factory setting: 0) applied

**(4) Queue attribute (wait\_queue)**

**Description:** Define the queue attribute regarding how tasks are queued waiting to send. Note that the receive queue is always managed in FIFO order.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_TFIFO : Queued in FIFO order
- TA\_TPRI : Queued in order of task priority

**When omitting:** The set value in default cfg file (factory setting: TA\_TFIFO) applied



## 8.4.8 mailbox Definition (mailbox[])

This definition item mailbox[] is provided for the definition (creation) of mailboxes.

### Format

```
mailbox[(1) ID number] {
    name                = (2) ID name;
    wait_queue         = (3) Queue attribute;
    message_queue      = (4) Message queue attribute;
    max_pri            = (5) Maximum priority of messages;
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Queue attribute (wait\_queue)

**Description:** Define the queue attribute regarding how tasks are queued waiting for the mailbox.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_TFIFO : Queued in FIFO order
- TA\_TPRI : Queued in order of task priority

**When omitting:** The set value in default cfg file (factory setting: TA\_TFIFO) applied

#### (4) Message queue attribute (message\_queue)

**Description:** Define the manner in which messages are tied to the message queue.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_MFIFO : Message queue in FIFO order
- TA\_MPRI : Message queue in order of message priority

**When omitting:** The set value in default cfg file (factory setting: TA\_MFIFO) applied

#### (5) Maximum priority of messages (max\_pri)

**Description:** If TA\_MPRI is specified for message\_queue, define the maximum priority of messages here.

**Definition range:** 1 to system.message\_pri

**When omitting:** The set value in default cfg file (factory setting: 1) applied

**Remark:** If message\_queue = TA\_MFIFO, this definition item has no effect.

## 8.4.9 Mutex Definition (mutex[])

The definition item mutex[] is provided for the definition (creation) of mutexes

### Format

```
mutex[(1) ID number] {
    name           = [(2) ID name];
    ceilpri        = [(3) Ceiling priority];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Ceiling priority (ceilpri)

**Description:** The mutexes in the RI600/4 are controlled by a priority ceiling protocol. Define this ceiling priority here.

**Definition format:** Numeric value

**Definition range:** 1 - system.priority

**When omitting:** The set value in default cfg file (factory setting: 1) applied

## 8.4.10 Message Buffer Definition (message\_buffer[])

The definition item message\_buffer[] is provided for the definition (creation) of message buffers.

### Format

```
message_buffer[(1) ID number] {
    name           = (2) ID name;
    mbf_size       = (3) Size of message buffer;
    mbf_section    = (4) Section name assigned to the message buffer area;
    max_msgsz     = (5) Maximum message size;
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Size of message buffer (mbf\_size)

**Description:** Specify the size of the message buffer in bytes. A message buffer which size is 0 can be created. In this case, the transmit and receive sides of the message buffer are fully synchronized when they communicate.

**Definition format:** Numeric value

**Definition range:** 0 or a multiple of 4 in the range 8 to 65,532

**When omitting:** The set value in default cfg file (factory setting: 0) applied

**(4) Section name assigned to the message buffer area (mbf\_section)**

**Description:** Define the section name to be assigned to the message buffer. The section attribute is "DATA", and the alignment number is 4.

When linking, be sure to locate this section in the RAM area.

**Definition format:** Symbol

**Definition range:** -

**When omitting:** The set value in default cfg file (factory setting: BRI\_HEAP) applied

**Remark:** If `mbf_size = 0`, this definition item has no effect.

**(5) Maximum message size (max\_msgsz)**

**Description:** Define the maximum message size in bytes. The specified value is rounded up to a multiple of 4. If `mbf_size > 0`, `max_msgsz` must be equal to or less than (`mbf_size - 4`).

**Definition format:** Numeric value

**Definition range:** 1 - 65528

**When omitting:** The set value in default cfg file (factory setting: 4) applied

### 8.4.11 Fixed-sized Memory Pool (memorypool[])

The definition item memorypool[] is provided for the definition (creation) of fixed-sized memory pools.

#### Format

```
memorypool [(1) ID number] {
    name           = (2) ID name;
    section        = (3) Section name assigned to the pool area (section);
    num_block      = (4) Number of memory blocks;
    siz_block      = (5) Memory block size;
    wait_queue     = (6) Queue attribute;
};
```

#### Contents

##### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

##### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

##### (3) Section name assigned to the pool area (section)

**Description:** Define the section name to be assigned to the pool area. The section attribute is "DATA", and the alignment number is 4.

When linking, be sure to locate this section in the RAM area.

**Definition format:** Symbol

**Definition range:** -

**When omitting:** The set value in default cfg file (factory setting: BRI\_HEAP) applied

**(4) Number of memory blocks (num\_block)**

**Description:** Define the number of blocks in the memory pool.

Note that the size of the memory pool area is determined by num\_block × siz\_block (bytes). The upper limit of the pool size is VTMAX\_AREASIZE (bytes).

**Definition format:** Numeric value

**Definition range:** 1 - 65535

**When omitting:** The set value in default cfg file (factory setting: 1) applied

**(5) Memory block size (siz\_block)**

**Description:** Define the memory block size in bytes.

**Definition format:** Numeric value

**Definition range:** 1 - 65535

**When omitting:** The set value in default cfg file (factory setting: 256) applied

**(6) Queue attribute (wait\_queue)**

**Description:** Define the queue attribute regarding how tasks are queued waiting for the memory block.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- TA\_TFIFO : Queued in FIFO order
- TA\_TPRI : Queued in order of task priority

**When omitting:** The set value in default cfg file (factory setting: TA\_TFIFO) applied

## 8.4.12 Variable-sized Memory Pool Definition (variable\_memorypool[])

The definition item variable\_memorypool[] is provided for the definition (creation) of variable-sized memory pools.

### Format

```
variable_memorypool[(1) ID number] {
    name                = [(2) ID name];
    mpl_section         = [(3) Section name assigned to the pool area (section)];
    heap_size           = [(4) Size of memory pool];
    max_memsize         = [(5) Upper limit of the memory block size];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Section name assigned to the pool area (mpl\_section)

**Description:** Define the section name to be assigned to the pool area. The section attribute is "DATA", and the alignment number is 4.

When linking, be sure to locate this section in the RAM area.

**Definition format:** Symbol

**Definition range:** -

**When omitting:** The set value in default cfg file (factory setting: BRI\_HEAP) applied



**(4) Size of memory pool (heap\_size)**

**Description:** Define the size of the memory pool in bytes. The specified value is rounded up to a multiple of 4.

**Definition format:** Numeric value

**Definition range:** 24 to VTMAX\_AREASIZE

**When omitting:** The set value in default cfg file (factory setting: 1024) applied

**(5) Upper limit of the memory block size (max\_memsize)**

**Description:** Define the upper limit of an acquirable memory block size in bytes.

The maximum size that can be actually acquired might become larger than max\_memsize.

**Definition format:** Numeric value

**Definition range:** 1 to 0xBFFFFFF4 (192MB - 12)

**When omitting:** The set value in default cfg file (factory setting: 36) applied

**Supplementation:** In the current implementation of the kernel, the memory block size actually acquired is either the variations (1 - 12 kind) selected from the following table. The cfg600 decides this variation based on heap\_size and max\_memsize. Note, this behavior might be changed in the future version.

No.	Memory block size (Hexadecimal)
1	12 (0xC)
2	36 (0x24)
3	84 (0x54)
4	180 (0xB4)
5	372 (0x174)
6	756 (0x2F4)
7	1524 (0x5F4)
8	3060 (0xBF4)
9	6132 (0x17F4)
10	12276 (0x2FF4)
11	24564 (0x5FF4)
12	49140 (0xBFF4)
13	98292 (0x17FF4)
14	196596 (0x2FFF4)
15	393204 (0x5FFF4)
16	786420 (0xBFFF4)
17	1572852 (0x17FFF4)
18	3145716 (0x2FFFF4)
19	6291444 (0x5FFFF4)
20	12582900 (0xBFFFF4)
21	25165812 (0x17FFFF4)
22	50331636 (0x2FFFFF4)
23	100663284 (0x5FFFFF4)
24	201326580 (0xBFFFFF4)

### 8.4.13 Cyclic Handler Definition (cyclic\_hand[])

The definition item cyclic\_hand[] is provided for the definition (creation) of cyclic handlers.

#### Format

```
cyclic_hand[(1) ID number] {
    name           = (2) ID name;
    entry_address  = (3) Handler entry address;
    interval_counter = (4) Activation cycle;
    start         = (5) Operating state of the cyclic handler;
    phsatr        = (6) Preservation of the activation phase;
    phs_counter   = (7) Activation phase;
    exinf         = (8) Extended information;
};
```

#### Contents

##### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

##### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

##### (3) Handler entry address (entry\_address)

**Description:** Define the entry address of the cyclic handler starting from which it is executed.

**Definition format:** Function name

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

##### (4) Activation cycle (interval\_counter)

**Description:** Define a cycle time in ms at which intervals the handler is activated.

**Definition range:** 1 - (0x7FFFFFFF - system.tic\_num) / system.tic\_deno

**When omitting:** The set value in default cfg file (factory setting: 1) applied

### (5) Operating state of the cyclic handler (start)

**Description:** Define the attribute regarding the handler's operating state.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- ON : Cyclic handler placed in an active state (TA\_STA attribute specified)
- OFF : Cyclic handler not placed in an active state (TA\_STA attribute not specified)

**When omitting:** The set value in default cfg file (factory setting: OFF) applied

### (6) Preservation of the activation phase (phsatr)

**Description:** Define the handler attribute regarding whether its activation phase is saved.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- ON : Activation phase saved (TA\_PHS attribute specified)
- OFF : Activation phase not saved (TA\_PHS attribute not specified)

**When omitting:** The set value in default cfg file (factory setting: OFF) applied

### (7) Activation phase (phs\_counter)

**Description:** Define the handler activation phase in ms. The activation phase must be equal to or less than the activation cycle.

**Definition format:** Numeric value

**Definition range:** 0 to (0x7FFFFFFF - system.tic\_nume) / system.tic\_deno

**When omitting:** The set value in default cfg file (factory setting: 0) applied

### (8) Extended information (exinf)

**Description:** Define the extended information of the cyclic handler.

**Definition format:** Numeric value

**Definition range:** 0 to 0xFFFFFFFF

**When omitting:** The set value in default cfg file (factory setting: 0) applied

## 8.4.14 Alarm Handler Definition (alarm\_hand[])

The definition item alarm\_hand[] is provided for the definition (creation) of alarm handlers.

### Format

```
alarm_hand[(1) ID number] {
    name           = [(2) ID name];
    entry_address  = [(3) Handler entry address];
    exinf          = [(4) Extended information];
};
```

### Contents

#### (1) ID number

**Description:** Define the ID number.

**Definition format:** Numeric value

**Definition range:** 1 - 255

**When omitting:** Automatically assigned the free ID numbers in order beginning with the smallest

**Note:** The ID numbers must be assigned without an omission beginning with 1. Therefore, when specifying an ID number, be sure that the specified value is equal to or less than the number of objects defined.

#### (2) ID name (name)

**Description:** Define the ID name. The specified ID name is output to the ID name header file (kernel\_id.h) in the form given below.

```
#define <ID name> <ID number>
```

**Definition format:** Symbol

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (3) Handler entry address (entry\_address)

**Description:** Define the entry address of the alarm handler starting from which it is executed.

**Definition format:** Function name

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

#### (4) Extended information (exinf)

**Description:** Define the extended information of the alarm handler.

**Definition format:** Numeric value

**Definition range:** 0 - 0xFFFFFFFF

**When omitting:** The set value in default cfg file (factory setting: 0) applied

### 8.4.15 Relocatable Vector Definition (interrupt\_vector[])

The definition item interrupt\_vector[] is used to define interrupt handlers for relocatable vectors.

If any interrupt occurs whose vector number is not defined here, the system goes down.

Note that cfg600 does not generate code to initialize the interrupt control registers (e.g., IPL), the causes of interrupts, etc. for the interrupts defined here. These initialization routines need to be created in the startup file or in any way deemed appropriate for the application developed by the user.

#### ☐ Attention

Please do not define interrupt handlers for MCU's reserved vector.

#### ☐ Format

```
interrupt_vector [(1) Vector number] {
    entry_address      = [(2) Handler entry address];
    os_int             = [(3) Kernel interrupt specification];
    pragma_switch     = [(4) Switch passed to PRAGMA extension function];
};
```

#### ☐ Contents

##### (1) Vector number

**Description:** Define the vector number of the interrupt that defines the handler.

**Definition format:** Numeric value

**Definition range:** 0 - 255

**When omitting:** Cannot be omitted (error assumed)

##### (2) Handler entry address (entry\_address)

**Description:** Define the entry address of the interrupt handler starting from which it is executed.

**Definition format:** Function name

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

### (3) Kernel interrupt specification (os\_int)

**Description:** Define whether the interrupt defined here is a kernel interrupt.

Interrupts whose priority level is lower than or equal to the kernel interrupt mask level (system.system\_IPL) must be handled as "kernel interrupt", and the other interrupts must be handled as "non-kernel interrupt".

Note, all relocatable interrupts must be handled as "kernel interrupt" when system.system\_IPL is 15.

**Definition format:** Symbol

**Definition range:** Select either of the following:

- YES : Kernel interrupt
- NO : Non-kernel interrupt

**When omitting:** Cannot be omitted (error assumed)

### (4) Switch passed to PRAGMA extension function (pragma\_switch)

**Description:** For the function specified by entry\_address, cfg600 outputs a #pragma interrupt declaration to kernel\_id.h as interrupt function. Specify the switch to be passed to this pragma declaration. For details about program specifications, see the compiler's manual.

**Definition format:** Symbol

**Definition range:** One of the following can be specified. To specify multiple choices, separate each with a comma.

- E: The "enable" switch that permits a multiple interrupt is passed.
- F: The "fint" switch that specifies a fast interrupt is passed. Note, a fast interrupt must be handled as non-kernel interrupt (os\_int=NO).
- S: The "save" switch that limits the number of registers used by the interrupt handler is passed.

**When omitting:** No switches are passed.

### 8.4.16 Fixed Vector Definition (interrupt\_fvector[])

The definition item `interrupt_fvector[]` is used to define the interrupt handlers for fixed vectors. The causes of fixed-vector interrupts are all handled as non-kernel interrupts.

Although the causes of fixed-vector interrupts in microcomputer specifications are not assigned vector numbers, the vector addresses in the RI600/4 each are assigned a vector number, as shown in Table 8.8.

If any interrupt except reset (#31) occurs whose vector number is not defined here, the system goes down.

When the vector #31 is not defined, the reset function is `PowerON_Reset_PC()`.

Table 8.8 Fixed vector number

Vector Address	Vector Number	Factor in RX610 Group
FFFFFF80H	0	(Reserved)
FFFFFF84H	1	(Reserved)
FFFFFF88H	2	(Reserved)
FFFFFF8CH	3	(Reserved)
FFFFFF90H	4	(Reserved)
FFFFFF94H	5	(Reserved)
FFFFFF98H	6	(Reserved)
FFFFFF9CH	7	(Reserved)
FFFFFFA0H	8	(Reserved)
FFFFFFA4H	9	(Reserved)
FFFFFFA8H	10	(Reserved)
FFFFFFACH	11	(Reserved)
FFFFFFB0H	12	(Reserved)
FFFFFFB4H	13	(Reserved)
FFFFFFB8H	14	(Reserved)
FFFFFFBCH	15	(Reserved)
FFFFFFC0H	16	(Reserved)
FFFFFFC4H	17	(Reserved)
FFFFFFC8H	18	(Reserved)
FFFFFFCCH	19	(Reserved)
FFFFFFD0H	20	Privileged instruction exception
FFFFFFD4H	21	(Reserved)
FFFFFFD8H	22	(Reserved)
FFFFFFDCH	23	Undefined instruction exception
FFFFFFE0H	24	(Reserved)
FFFFFFE4H	25	Floating-point exception
FFFFFFE8H	26	(Reserved)
FFFFFFECH	27	(Reserved)
FFFFFFF0H	28	(Reserved)
FFFFFFF4H	29	(Reserved)
FFFFFFF8H	30	Non-maskable interrupt
FFFFFFFCH	31	Reset

Note that `cfg600` does not generate code to initialize the interrupt control registers (e.g., IPL), the causes of interrupts, etc. for the interrupts defined here. These initialization routines need to be created in the startup file or in any way deemed appropriate for the application developed by the user.

## □ Attention

Please do not define interrupt handlers for MCU's reserved vector.

## □ Format

```
interrupt_fvector[(1) Vector number] {
    entry_address      = [(2) Handler entry address];
    pragma_switch      = [(3) Switch passed to PRAGMA extension function];
};
```

## □ Contents

### (1) Vector number

**Description:** Define the vector number of each interrupt referring to Table 8.8.

**Definition format:** Numeric value

**Definition range:** 0 - 31

**When omitting:** Cannot be omitted (error assumed)

### (2) Handler entry address (entry\_address)

**Description:** Define the entry address of the interrupt handler starting from which it is executed.

**Definition format:** Function name

**Definition range:** -

**When omitting:** Cannot be omitted (error assumed)

### (3) Switch passed to PRAGMA extension function (pragma\_switch)

**Description:** For the function specified by entry\_address, cfg600 outputs a #pragma interrupt declaration to kernel\_id.h as interrupt function. Specify the switch to be passed to this pragma declaration. For details about program specifications, see the compiler's manual.

Note, #pragma interrupt is not generated, if vector number is 31 (reset).

**Definition format:** Symbol

**Definition range:** Following can be specified.

- S: The "save" switch that limits the number of registers used by the interrupt handler is passed.

**When omitting:** No switches are passed.



## 8.5 Executing the Configurator

### 8.5.1 Outline of the Configurator

The configurator is the tool that based on the content defined in the cfg file, outputs various system definition files and the header files used for the application. Following files are output by executing the configurator.

- ID number header file (kernel\_id.h)  
This file defines the ID numbers of kernel objects.
- Service call definition file (kernel\_sysint.h)  
This is the declaration file needed to invoke service calls using the INT instruction. This file is included from kernel.h.
- System definition files (kernel\_rom.h, kernel\_ram.h, ri600.inc)  
The file kernel\_rom.h and kernel\_ram.h must be included by startup file. Please refer to Section 7.2, "Creating Startup File (resetprg.c)."  
The file ri600.inc is included from the ritable.src that is generated by mkritbl.
- Vector table template file (vector.tpl)  
The vector.tpl is loaded into mkritbl.
- CMT definition file (ri\_cmt.h)  
When one of CMT0, CMT1, CMT2 or CMT3 is specified for clock.timer, the file indicated by clock.template retrieved from the directory defined by environment variable "LIB600", and the file is copied and renamed to "ri\_cmt.h".  
The ri\_cmt.h is included by startup file.

The outline operation of the configurator is shown in Figure 8.1.

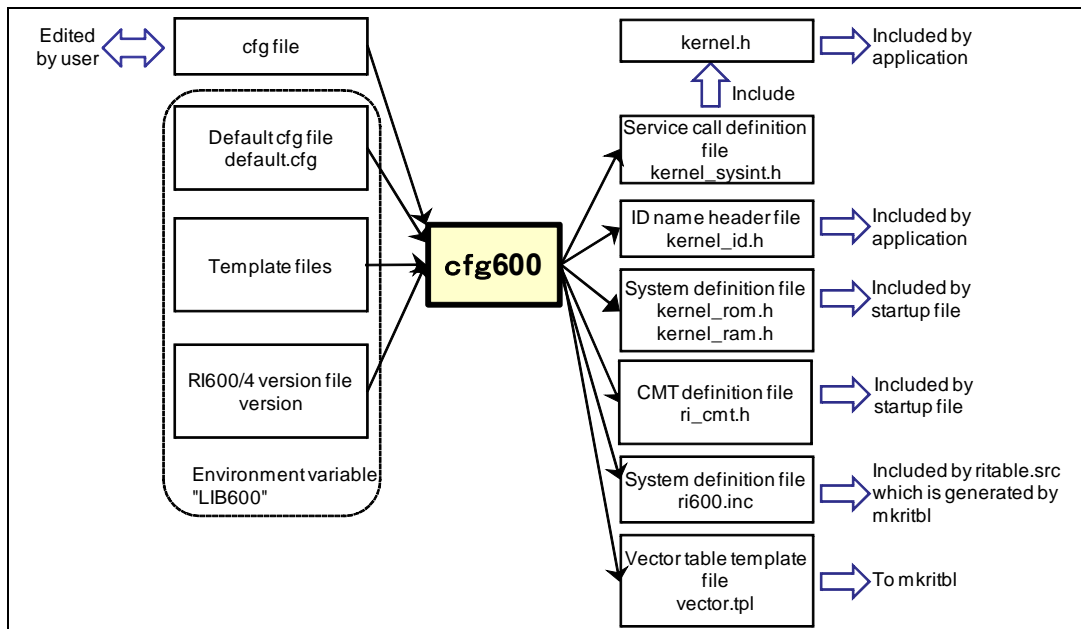


Figure 8.1 Outline Operation of the Configurator

## 8.5.2 Environment Settings

Following environment variables need to be set.

- LIB600  
"<Installation directory>\lib600"

## 8.5.3 Configurator Start Procedure

The configurator is started in the form shown below.

```
cfg600[Δ<option>...][Δ<cfg file name>]
```

If the filename extension of the cfg file is omitted, the extension ".cfg" is assumed.

## 8.5.4 Command Options

### (1) -U option

When an undefined interrupt occurs, a system-down results. When -U option is specified, the vector number will be transferred to the system-down routine. This is useful for debugging. However, the kernel code size increases by about 1.5 kB.

### (2) -v option

Shows a description of the command option and details of its version.

### (3) -V option

Shows the creation status of files generated by the command.

## 8.6 Errors Messages

### 8.6.1 Error Output Format and Error Levels

This section describes the meaning of the error messages output in the following format.

```
Error number (Error level) Error message
```

Errors are classified into two levels as shown in Table 8.9.

Table 8.9 Error Levels

Error level		Operation
(W)	Warning	Continues processing.
(E)	Error	Aborts processing.

### 8.6.2 List of Messages

#### (1) Error Messages

```
01001 (E) Syntax error
    Syntax error.
01002 (E) Illegal XXX --> <setting>
    The setting for definition name XXX is illegal.
01003 (E) Unknown token --> <XXX>
    The specified strings cannot be recognized as a definition name.
01004 (E) XXX's ID number is too large.--> <ID>
    The ID specified for XXX[] is too large. The ID should be smaller than or equal to the number of
    definitions of XXX[].
01005 (E) Task[1]'s priority is too large. --> <setting>
    task[].priority exceeds system.priority.
01006 (E) clock.IPL is too large.--> <setting>
    clock.IPL exceeds system.system_IPL.
01007 (E) System timer's vector <XXX> conflict
    A interrupt_vector[] has already defined for the CMT's vector when one of CMT0, CMT1, CMT2, or
    CMT3 is specified for clock.timer.
01009 (E) XXX is already defined.
    XXX has already been defined.
01010 (E) XXX[YYY] is already defined.
    XXX[YYY] has already been defined.
01013 (E) Zero divide error
    Zero division expression.
01015 (E) Can't specify F switch when os_int=YES.
```

- "F" switch cannot be specified for kernel interrupt handler.
- O1016 (E) interrupt\_vector[YYY].os\_int must be YES.  
Relocatable interrupt cannot be used as kernel interrupt when the kernel interrupt mask level (system.system\_IPL) is 15.
- O1018 (E) mailbox[YYY].max\_pri(setting) is bigger than system.message\_pri(setting).  
mailbox.max\_pri must be lower than or equal to system.message\_pri.
- O1019 (E) Neither system.tic\_nume nor system.tic\_deno is 1.  
Neither system.tic\_nume nor system.tic\_deno is 1.
- O1020 (E) Symbols other than NO and NO are defined simultaneously.  
Symbols other than NO and NO are defined simultaneously.
- O1022 (E) semaphore[YYY].initial\_count is bigger than semaphore[YYY].max\_count  
semaphore[YYY].initial\_count is bigger than semaphore[YYY].max\_count.
- O1023 (E) Size of memorypool[YYY] is larger than VTMAX\_AREASIZE  
The size of fixed-sized memory pool must be lower than or equal to VTMAX\_AREASIZE (256MB).
- O1024 (E) variable\_memorypool[YYY].max\_memsize is larger than 192MB-12  
variable\_memorypool.max\_memsize must be lower than or equal to "192MB-12".
- O1025 (E) mutex[YYY].ceilpri is bigger than system.priority.  
mutex.ceilpri must be lower than or equal to system.priority.
- O1026 (E) XXX is not a multiple of 4.  
XXX must be multiple of 4.
- O1027 (E) max\_msgsz (setting) is larger than mbf\_size(setting) - 4 .  
message\_buffer.max\_msgsz must be lower than or equal to message\_buffer.mbf\_size-4.
- O1028 (E) variable\_memorypool[YYY].max\_memsize is too large. (Max.=ZZZ)  
The value YYY specified for variable\_memorypool[YYY].max\_memsize is too large. The maximum value of max\_memsize that can be specified for heap\_size is ZZZ.
- O1029 (E) Timer tick is too long.  
Time-tick cycle decided by system.tic\_nume and system.tic\_deno is too long. Shorten timer-tick or lower clock.timer\_clock.
- O1030 (E) Timer tick is too short.  
Time-tick cycle decided by system.tic\_nume and system.tic\_deno is too short. Lengthen timer-tick or higher clock.timer\_clock.
- O2001 (E) Not enough memory  
Insufficient memory.
- O2003 (E) Illegal argument --> <XXX>  
The startup format has an error.
- O2004 (E) Can't write open <file name>  
The file cannot be generated.
- O2005 (E) Can't open <file name>  
The file cannot be accessed in the directory indicated by environment variable "LIB600".
- O2006 (E) Can't open version file  
The version file cannot be found in the current directory or the directory indicated by environment

variable "LIB600".

O2007(E) Can't open default configuration file

The default.cfg file cannot be found in the current directory or the directory indicated by environment variable "LIB600".

O2008(E) Can't open configuration file <file name>.

The specified cfg file cannot be accessed.

O2009(E) XXX not defined

(1) XXX is not defined.

(2) The definition of the object of the displayed number leaks. This error occurs with O1004.

O2010(E) Initial start task is not defined.

There is no task[] definition with initial\_start=ON.

O2011(E) Environment variable "LIB600" not prepared.

Environment variable "LIB600" is not set.

## (2) Warning Messages

O3001(W) XXX is already defined.

XXX has already been defined. The definition is ignored.

O4001(W) XXX is not defined.

The definition of XXX is omitted; the setting in the default cfg file is used.

O4005(W) Timer counter value is less than your setting time

The specified timer cycle ( = system.tic\_num / system.tic\_deno [ms] ) cannot be achieved without the error margin. Actual time of cycle is shorter than the specified time of the cycle.

## 9. Table Generation Utility (mkritbl)

### 9.1 Summary

The utility mkritbl is a command line tool that after collecting service call information used in the application, generates service call tables and interrupt vector tables.

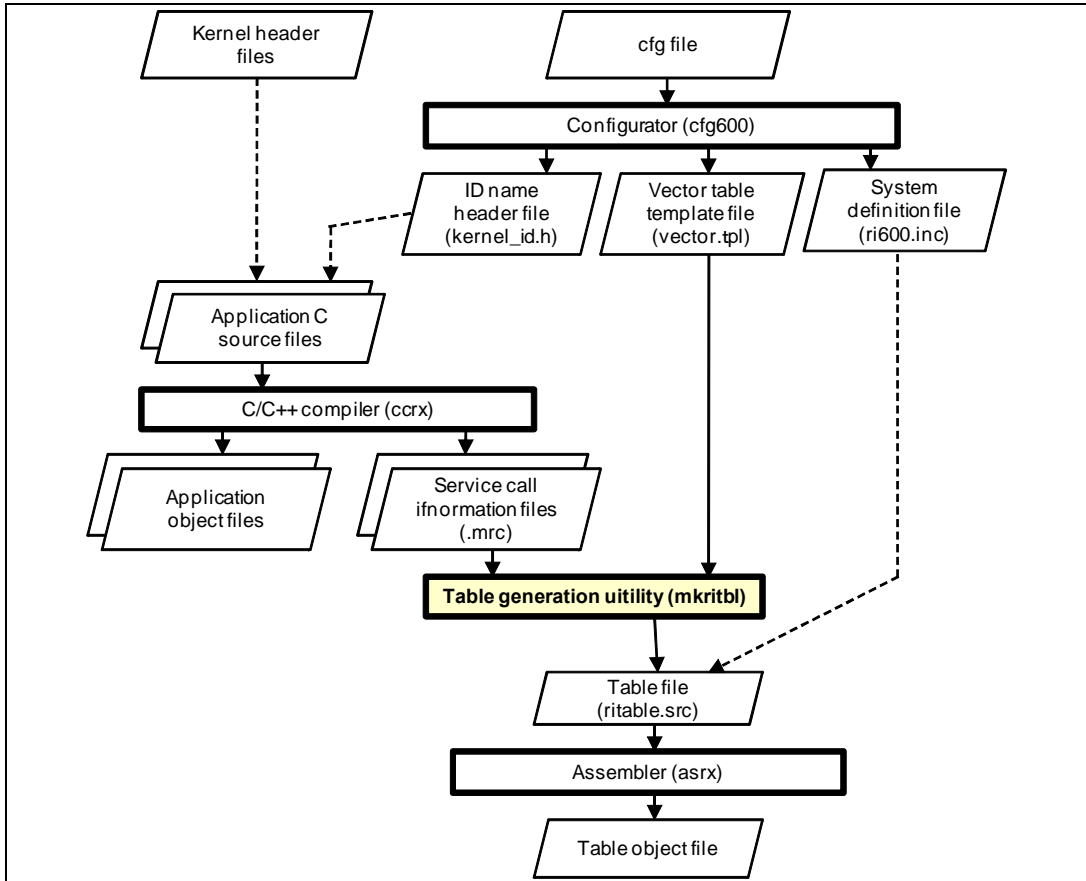


Figure 9.1 Outline of mkritbl

In `kernel_sysint.h` that is included by `kernel.h`, it is so defined that when service call functions are used, the service call information will be output to the `.mrc` file by the `.assert` control instruction. Using these service call information files as its input, `mkritbl` generates a service call table in such a way that only the service calls used in the system will be linked.

Furthermore, `mkritbl` generates an interrupt vector table based on the vector table template files output by `cfg600` and the `.mrc` file.

## 9.2 Environment Setup

Following environment variables need to be set.

- LIB600  
"<Installation directory>\lib600"

## 9.3 Table Generation Utility Start Procedure

The table generation utility is started in the form shown below.

```
C:\> mkritbl <directory name or file name>
```

For the parameter, normally specify the directory that contains the mrc file that is generated when compiled. Multiple directories or files can be specified.

Note that the mrc file present in the current directory is unconditionally selected for input.

Also, it is necessary that vector.tpl generated by cfg600 be present in the current directory.

## 9.4 Notes

Please specify mrc files generated by compilation of application without omission. If some service call modules might not be build into the load module when there is an omission in the specification of mrc files, When unlinked service call is issued, the system will go down.



---

## 10. GUI Configurator

---

The GUI configurator is a tool that permits the user to generate cfg files by entering various kernel configuration information from GUI screen. The cfg files thus generated are input to cfg600.

Using the GUI configurator, it is possible to build the kernel without the need for learning how to write a cfg file.

Figure 10.1 shows the relationship between the GUI configurator and the cfg file and cfg600.

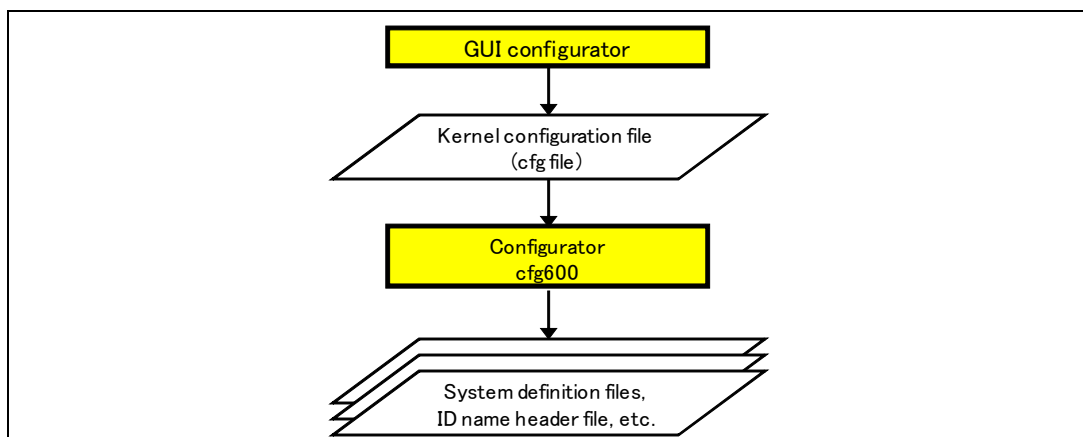


Figure 10.1 Relationship between the GUI Configurator and the cfg File and cfg600

See online help for details on how to use the GUI configurator.

---

# 11. Sample Program

---

## 11.1 Overview

As an example application of RI600/4, the following shows a program that outputs a string to the standard output device from one task and another alternately.

Table 11.1 Functions in the Sample Program

Function	Type	ID number	Task priority	Description
main()	Task	1	1	Activates task1 and task2 and cyh1
task1()	Task	2	2	Outputs "task1 running"
task2()	Task	3	3	Outputs "task2 running"
cyh1()	Cyclic handler	1	-	Wakes up task1

The content of processing is described below.

- The main task activates task1, task2, and cyh1, and then terminates itself.
- The task1 operates in order to following.
  1. Acquires a semaphore (wai\_sem)
  2. Sleep (slp\_tsk)
  3. Outputs "task1 running"
  4. Releases a semaphore (sig\_sem)
- The task2 operates in order to following.
  1. Acquires a semaphore (wai\_sem)
  2. Outputs "task2 running"
  3. Releases a semaphore (sig\_sem)
- The cyh1 starts every 100 [millisecond] to wake up the task1 (iwup\_tsk).

## 11.2 Source Listing

```
1 /*****
2 *
3 *          RI600/4 sample program
4 *****/
5 #include <stdio.h>
6 #include "kernel.h"
7 #include "kernel_id.h"
8
9
10 void task1( VP_INT exinf)
11 {
12     while(1){
13         wai_sem(ID_SEM1);
14         slp_tsk();
15         printf("task1 running\n");
16         sig_sem(ID_SEM1);
17     }
18 }
19
20 void task2( VP_INT exinf)
21 {
22     while(1){
23         wai_sem(ID_SEM1);
24         printf("task2 running\n");
25         sig_sem(ID_SEM1);
26     }
27 }
28
29 void cyh1( VP_INT exinf )
30 {
31     iwup_tsk(ID_TASK1);
32 }
```

## 11.3 Sample cfg File

```

1 //*****
2 //      RI600/4 System Configuration File.
3 //*****
4
5 // System Definition
6 system{
7     stack_size = 1024;
8     priority   = 10;
9     system_IPL = 4;
10    message_pri = 10;
11    tic_num     = 1;
12    tic_deno    = 1;
13    context     = NO;
14 };
15 //System Clock Definition
16 clock{
17     timer_clock = 25MHz;
18     timer       = CMT0;
19     IPL         = 4;
20 };
21 //Task Definition
22 task[] {
23     name        = ID_TASK1;
24     entry_address = task1();
25     initial_start = ON;
26     stack_size  = 512;
27     priority    = 1;
28 };
29 task[] {
30     name        = ID_TASK2;
31     entry_address = task2();
32     initial_start = ON;
33     stack_size  = 512;
34     priority    = 2;
35 };
36 // Semaphore Definition
37 semaphore[] {
38     name        = ID_SEM1;
39     max_count   = 1;
40     initial_count = 1;
41     wait_queue  = TA_TPRI;
42 };
43 // Cyclic Handler Definition
44 cyclic_hand[] {
45     name        = ID_CYC1;
46     entry_address = cyh1();
47     interval_counter = 100;
48     start       = ON;
49     phsatr      = OFF;
50     phs_counter = 0;
51     exinf       = 1;
52 };

```

---

## 12. Method for Calculating the Stack Size

---

### 12.1 Types of Stacks

There are two types of stacks: the system stack and the user stack. The method for calculating stack sizes differs between the system stack and user stack.

- User stack  
The stacks for tasks are referred to as the user stack. The user stack needs to be reserved individually for each stack. The user stack size of each task is specified by `task[].stack_size` in the `cfg` file.  
Also, the user stack for each task can be allocated to separate sections by `task[].stack_section`. The user stack is accessed by the CPU's USP register.
- System stack  
There is only one stack in the system, provided for other than tasks, that is used in common by various handlers and the kernel. The system stack size is specified by `system.stack_size` in the `cfg` file. The section name is "SI".  
The system stack is accessed by the CPU's ISP register.

### 12.2 "Call Walker"

The compiler package includes "Call Walker" which is a utility tool to calculate stack size.

The Call Walker can display stack size used by each function tree.

## 12.3 Calculating the User Stack Size of Each Task

The user stack size of each task can be calculated by the following expression.

$$\text{Necessary size of the user stack} = \alpha + \beta$$

$\alpha$ :

Size consumed by function tree that makes the task entry function starting point. (The size displayed by Call Walker)

$\beta$ : Task context size

Task context size is different according to system.context defined in the cfg file. See Table 12.1.

Table 12.1 Task context size

system.context	Task context size (bytes)
NO	68
FPSW	72
ACC	76
FPSW,ACC	80
MIN	44
MIN,FPSW	48
MIN,ACC	52
MIN,FPSW,ACC	56

## 12.4 Calculating the System Stack Size

The system stack is most often consumed when an interrupt occurs during service call processing followed by the occurrence of multiple interrupts.<sup>5</sup> The necessary size (the maximum size) of the system stack can be obtained from the following relation:

$$\text{Necessary size of the system stack} = \alpha + (\sum \beta_i) + \gamma$$

$\alpha$ :

The maximum size among the service calls to be used. The value  $\alpha$  depends on the kernel version. See release notes of the product attachment.

$\beta_i$ :

Size consumed by function tree that makes the interrupt handler entry function starting point. (The size displayed by Call Walker)

The "i" is interrupt priority level. If there are multiple interrupts in the same priority level, the  $\beta_i$  should select the maximum size among the handlers.

The size used by the system clock interrupt handler (the interrupt priority level is specified by `clock.clocl_IPL` in the `cfg` file) is the following maximum values. Please refer to the release notes for  $\epsilon_1$ ,  $\epsilon_2$  and  $\epsilon_3$ .

Don't have to add the size used by the system clock interrupt handler to the system stack size when system timer is not used (`clock.timer = NOTIMER`).

- $\epsilon_1 + \text{CYC}$
- $\epsilon_2 + \text{ALM}$
- $\epsilon_3$

◆ **CYC**

Size consumed by function tree that makes the cyclic handler entry function starting point. (The size displayed by Call Walker)

If there are multiple cyclic handlers, the CYC should select the maximum size among the handlers

◆ **ALM**

Size consumed by function tree that makes the alarm handler entry function starting point. (The size displayed by Call Walker)

If there are multiple alarm handlers, the ALM should select the maximum size among the handlers

$\gamma$ :

Size consumed by function tree that makes the system down routine entry function starting point. (the size displayed by Call Walker) + 40. When the system down routine has never been executed,  $\gamma$  is assumed to be 0.

<sup>5</sup> After switchover from user stack to system stack

---

**Real-time OS for RX600 Series**  
**User's Manual**  
**RI600/4 V.1.00**

Publication Date: 1st Edition, August 28, 2009  
Published by: Sales Strategic Planning Div.  
Renesas Technology Corp.  
Edited by: Customer Support Department  
Global Strategic Communication Div.  
Renesas Solutions Corp.

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RI600/4 V.1.00  
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REJ10J2052-0100